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U.S. DEPARTMENT OF COMMERCE PATENT AND TRADEMARK OFFICE

ATTORNEY'S DOCKET NUMBER

## TRANSMITTAL LETTER TO THE UNITED STATES

TNAB-T0158

DESIGNATED/ELECTED OFFICE (DO/EO/US)

U.S. APPLICATION NO. OF RECORD IN SET 7 (PCT/PTO)

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09/646849  
PCT/PTO 22 SEP 2000

INTERNATIONAL APPLICATION NO.

INTERNATIONAL FILING DATE

PRIORITY DATE CLAIMED

PCT/JP00/00754

10 February 2000 (10.02.00)

10 February 1999 (10.02.99)

## TITLE OF INVENTION

APPARATUS AND METHOD FOR JOINT MECHANISM, JOINT APPARATUS, AND ROBOT DEVICE AND CONTROL METHOD THEREOF

APPLICANT(S) FOR DO/EO/US

ISHIDA, Tatsuzo; HATTORI, Yuichi; and KUROKI, Yoshihiro

Applicant herewith submits to the United States Designated/Elected Office (DO/EO/US) the following items and other information:

1. ☒ This is a **FIRST** submission of items concerning a filing under 35 U.S.C. 371.
2. ☐ This is a **SECOND** or **SUBSEQUENT** submission of items concerning a filing under 35 U.S.C. 371.
3. ☒ This is an express request to begin national examination procedures (35 U.S.C. 371(f)) at any time rather than delay examination until the expiration of the applicable time limit set in 35 U.S.C. 371(b) and PCT Articles 22 and 39(1).
4. ☐ A proper Demand for International Preliminary Examination was made by the 19th month from the earliest claimed priority date.
5. ☒ A copy of the International Application as filed (35 U.S.C. 371 (c) (2))
  - a. ☐ is transmitted herewith (required only if not transmitted by the International Bureau).
  - b. ☒ has been transmitted by the International Bureau.
  - c. ☐ is not required, as the application was filed in the United States Receiving Office (RO/US).
6. ☒ A translation of the International Application into English (35 U.S.C. 371(c)(2)).
7. ☒ A copy of the International Search Report (PCT/ISA/210). (In English and Japanese)
8. ☐ Amendments to the claims of the International Application under PCT Article 19 (35 U.S.C. 371 (c)(3))
  - a. ☐ are transmitted herewith (required only if not transmitted by the International Bureau).
  - b. ☐ have been transmitted by the International Bureau.
  - c. ☐ have not been made; however, the time limit for making such amendments has NOT expired.
  - d. ☒ have not been made and will not be made.
9. ☐ A translation of the amendments to the claims under PCT Article 19 (35 U.S.C. 371(c)(3))
10. ☒ An oath or declaration of the inventor(s) (35 U.S.C. 371 (c)(4)). (unsigned)
11. ☐ A copy of the International Preliminary Examination Report (PCT/IPEA/409).
12. ☐ A translation of the annexes to the International Preliminary Examination Report under PCT Article 36 (35 U.S.C. 371 (c)(5)).

## Items 13 to 20 below concern document(s) or information included:

13. ☒ An Information Disclosure Statement under 37 CFR 1.97 and 1.98. with Form PTO 1449 and cited prior art.
14. ☐ An assignment document for recording. A separate cover sheet in compliance with 37 CFR 3.28 and 3.31 is included.
15. ☒ A **FIRST** preliminary amendment.
16. ☐ A **SECOND** or **SUBSEQUENT** preliminary amendment.
17. ☐ A substitute specification.
18. ☐ A change of power of attorney and/or address letter.
19. ☒ Certificate of Mailing by Express Mail
20. ☒ Other items or information:

- a.) Twenty-two (22) sheets of formal drawings including one page explanation of reference numerals;
- b.) Forms PCT/IB/301, 304 and 308;
- c.) PCT Request as filed;
- d.) Copy of Front Page of Certified Copy of Japanese priority documents No. P11-033385 filed February 10, 1999 and No. P11-254880 filed September 8, 1999.
- e.) Forms PCT/RO/105 and PCT/RO/106;
- f.) Form PCT/ISA/202; and
- g.) International application as published on August 17, 2000 as WO00/47372.

U.S. APPLICATION NO. (IF KNOWN, SEE 37 CFR 1.5)

INTERNATIONAL APPLICATION NO.

ATTORNEY'S DOCKET NUMBER

09/646849

PCT/JP00/00754

TNAB-T0158

21. The following fees are submitted:

**BASIC NATIONAL FEE ( 37 CFR 1.492 (a) (1) - (5) ) :**

- ☐ Neither international preliminary examination fee (37 CFR 1.482) nor international search fee (37 CFR 1.445(a)(2)) paid to USPTO and International Search Report not prepared by the EPO or JPO ..... \$970.00
- ☒ International preliminary examination fee (37 CFR 1.482) not paid to USPTO but International Search Report prepared by the EPO or JPO ..... \$840.00
- ☐ International preliminary examination fee (37 CFR 1.482) not paid to USPTO but international search fee (37 CFR 1.445(a)(2)) paid to USPTO ..... \$690.00
- ☐ International preliminary examination fee paid to USPTO (37 CFR 1.482) but all claims did not satisfy provisions of PCT Article 33(1)-(4) ..... \$670.00
- ☐ International preliminary examination fee paid to USPTO (37 CFR 1.482) and all claims satisfied provisions of PCT Article 33(1)-(4) ..... \$96.00

**ENTER APPROPRIATE BASIC FEE AMOUNT =****\$840.00**

Surcharge of **\$130.00** for furnishing the oath or declaration later than ☐ 20 ☐ 30 months from the earliest claimed priority date (37 CFR 1.492 (e)).

**\$0.00**

CLAIMS	NUMBER FILED	NUMBER EXTRA	RATE
Total claims	17 - 20 =	0	x \$18.00
Independent claims	8 - 3 =	5	x \$78.00

**\$0.00****\$390.00**Multiple Dependent Claims (check if applicable). ☐**\$0.00****TOTAL OF ABOVE CALCULATIONS =****\$1,230.00**

Reduction of 1/2 for filing by small entity, if applicable. Verified Small Entity Statement must also be filed (Note 37 CFR 1.9, 1.27, 1.28) (check if applicable). ☐

**\$0.00****SUBTOTAL =****\$1,230.00**

Processing fee of **\$130.00** for furnishing the English translation later than ☐ 20 ☐ 30 months from the earliest claimed priority date (37 CFR 1.492 (f)).

**\$0.00****TOTAL NATIONAL FEE =****\$1,230.00**

Fee for recording the enclosed assignment (37 CFR 1.21(h)). The assignment must be accompanied by an appropriate cover sheet (37 CFR 3.28, 3.31) (check if applicable). ☐

**\$0.00****TOTAL FEES ENCLOSED =****\$1,230.00**

Amount to be:

refunded

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\$

- ☒ A check in the amount of **\$1,230.00** to cover the above fees is enclosed
- ☐ Please charge my Deposit Account No. \_\_\_\_\_ in the amount of \_\_\_\_\_ to cover the above fees.  
A duplicate copy of this sheet is enclosed.
- ☒ The Commissioner is hereby authorized to charge any fees which may be required, or credit any overpayment to Deposit Account No. **12-1420** A duplicate copy of this sheet is enclosed.

**NOTE: Where an appropriate time limit under 37 CFR 1.494 or 1.495 has not been met, a petition to revive (37 CFR 1.137(a) or (b)) must be filed and granted to restore the application to pending status.**

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SIGNATURE

Mayumi Maeda

NAME

40,075

REGISTRATION NUMBER

September 22, 2000

DATE

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PATENT

-1-

IN THE UNITED STATES PATENT AND TRADEMARK OFFICE

In re Application of ) Group Art Unit: Unknown  
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TATSUZO ISHIDA ET AL. ) Examiner: Unknown  
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Application No. Not Assigned ) PRELIMINARY AMENDMENT  
)  
Filed: Herewith ) 2001 Ferry Bldg.  
) San Francisco, CA 94111  
For: APPARATUS AND METHOD ) Ph.: 415-433-4150  
FOR JOINT MECHANISM, )  
JOINT APPARATUS, AND )  
ROBOT DEVICE AND )  
CONTROL METHOD )  
THEREOF )  
\_\_\_\_\_ )

Box PCT  
Assistant Commissioner for Patents  
Washington, D.C. 20231

Sir:

Prior to examination of the above-identified application, please enter  
the following amendments:

In the Specification

Page 7, line 19, please change "Fig. 4 is a front view and a side view"  
to --Figs. 4(a) and 4(b) are a front view and a side view respectively,  
showing--;

Page 7, line 21, please change "Fig. 5 is a front view and an oblique view" to --Figs. 5(a) and 5(b) are a front view and an oblique view, respectively, showing--;

Page 7, line 23, please change "Fig. 6 is a side view, a front view, and a side view" to --Figs. 6(a), 6(b) and 6(c) are a side view, a front view, and a side view, respectively--;

Page 7, line 23, please change "Fig. 6 is a side view, a front view, and a side view" to --Figs. 6(a), 6(b) and 6(c) are a side view, a front view, and a side view, respectively--;

Page 8, line 7, please change "Fig. 10 shows" to --Figs. 10(a), 10(b) and 10(c) show--;

Page 8, line 11, please change "Fig. 12 shows" to --Figs. 12(a), 12(b) and 12(c) show--;


Page 8, line 13, please change "Fig. 13 shows" to --Figs. 13(a), 13(b) and 13(c) show--;

Page 8, line 20, please change "Fig. 16 is a plan view" to --Figs. 16(a) and 16(b) are plans views--;

#### REMARKS

The amendments to the specification and drawings are to conform the drawings to the specification, to conform the specification to the drawings and/or correct typographical errors. It is respectfully submitted that such amendments are supported by the specification, claims, abstract of the disclosure and the drawings.

The Examiner's early examination and consideration are respectfully requested.

By:   
Mayumi Maeda  
Reg. No. 40,075

September 22, 2000  
Our File: TNAB-T0158

22/PRTS

09/646849

534 Rec'd PCT/PTG 22 SEP2000

DESCRIPTION

APPARATUS AND METHOD FOR JOINT MECHANISM, JOINT APPARATUS, AND  
ROBOT DEVICE AND CONTROL METHOD THEREOF

Technical Field

The present invention relates to the joint mechanism control apparatus and method, the joint apparatus, the robot device and the method for controlling the robot device, and can be appropriately applied to, for example, a two-leg walking robot.

Background Art

Conventionally, a two-leg walking robot is designed by connecting a pair of leg units to a belly unit through a thigh joint mechanism. Each leg unit is formed by connecting a thigh unit to a lower leg unit through a knee joint mechanism, and by connecting a foot unit to the lower leg unit through an ankle joint mechanism.

This two-leg walking robot has an actuator (normally an AC (Alternating Current) serve-motor hereinafter referred to as a motor) incorporated for a necessary free level for each joint mechanism. Each motor of each joint mechanism can be individually driven and controlled such that each leg unit can be driven in a predetermined pattern, thereby performing a walking operation as a complete robot.

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In the above described two-leg walking robot, various sensors such as a pressure sensor, a tilt angle sensor, an acceleration sensor, a micro switch, etc. are provided at an ankle joint mechanism or a foot unit. The two-leg walking robot is designed to stably walk even on the unlevelled ground with tilt or convexity/concavity by controlling the direction of the foot units such that the reverse surfaces of the foot units can always follow the surface of the walkway based on the outputs from the above described sensors in the walking operation.

However, when such a sensor is actually provided for the ankle joint mechanism and the leg unit, the total weight of an entire robot increases by the weight of the sensor. In addition, wiring is required to electrically connect the sensors with a control system in the robot, thereby causing the problem of a complicated configuration of the entire robot. Furthermore, if a sensor is mounted, it is necessary to process sensor information using software in a control system in the robot, thereby complicating the walking control.

With the conventional 2-leg walking robot, for example, as shown in Fig. 23, a main control unit 1 for controlling the operations of the entire robot is connected to each motor 3 (3-1 through 3-n) through a multi-axis controller 2, and the multi-axis controller 2 controls each motor 3 in each specific state at a control instruction output from the main control unit 1.

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In the above described two-leg walking robot, three rotation drive cables (U phase, V phase, and W phase), four rotation position sensor cables (A phase, B phase, and Z phase), and one ABS position serial signal cable, that is, a total of seven cables 4, are required, thereby causing the problem of a complicate configuration containing a larger number of wires for the entire robot.

#### Disclosure of the Invention

The present invention has been developed to solve the above described problems, and aims at providing an apparatus and a method for controlling the joint mechanism capable of simplifying the configuration, a joint apparatus and a robot device and a control method thereof.

To solve the above described problem, the joint mechanism control device according to the present invention includes: electric current detection means for detecting an electric current value of the drive current of an actuator for driving a joint mechanism; and external force torque detection means for detecting the level of the torque by an external force applied to the output axis of the actuator based on the electric current value detected by the electric current detection unit.

As a result, according to the control device, the external force applied to the first or the second link can be obtained without any sensor, etc. Thus, a sensor, etc. for directly

measuring the external force can be omitted, thereby realizing a joint mechanism control device with a simple entire configuration.

In addition, the method of controlling the joint mechanism according to the present invention includes: a first step of detecting an electric current value of the drive current of the actuator for driving a joint mechanism; and a second step of detecting the level of the torque by an external force applied to the output axis of the actuator based on the detected electric current value.

As a result, in the control method, the external force applied to the first or the second link can be obtained without a sensor, etc. Thus, a sensor, etc. for directly measuring the external force can be omitted, thereby realizing a joint mechanism control device with a simple entire configuration of the joint mechanism.

Furthermore, the robot device according to the present invention includes: electric current detection means for detecting an electric current value of the drive current of an actuator of a joint mechanism; and external force torque detection means for detecting the level of the torque by an external force applied to the output axis of the actuator based on the electric current value detected by the electric current detection unit.

As a result, according to the robot device, the external force applied to the first or the second component can be obtained without a sensor, etc. Thus, a sensor, etc. for directly

measuring the external force can be omitted, thereby realizing a robot device with a simple entire configuration.

Furthermore, the robot device control method according to the present invention includes: a first step of detecting an electric current value of the drive current of the actuator; and a second step of detecting the level of the torque by an external force applied to the output axis of the actuator based on the detected electric current value.

As a result, in the robot device control method, the external force applied to the first or the second component can be obtained without any sensor, etc. As a result, a sensor, etc. for directly measuring the external force can be omitted, thereby realizing a robot device control method with a simple entire configuration of the robot device.

Furthermore, according to the present invention, the two-leg walking robot device includes: an actuator, provided at the ankle joint mechanism, for generating the rotation torque at a level depending on a drive current; an electric current detection unit for detecting the electric current value of the drive current of the actuator; an external force torque detection unit for detecting the level of the torque generated by an external force by the output axis of the actuator based on the electric current value detected by the electric current detection unit; and a control unit for controlling the actuator based on the detection result of the external force torque detection unit such that the

torque generated by the external force provided for the output axis of the actuator can be removed.

As a result, the robot device realizes walking without a sensor, etc. with good balance on the unlevelled ground, thereby realizing a robot device with a simple entire configuration.

In addition, according to the present invention, the method of controlling a two-leg walking robot device includes: a first step of detecting the electric current value of the drive current of an actuator, provided at the ankle joint mechanism, for generating the rotation torque at a level depending on a drive current; a second step of detecting the level of the torque generated by an external force by the output axis of the actuator based on the detected electric current value; and a third step of controlling the actuator based on the detection result obtained in the second step such that the torque generated by the external force provided for the output axis of the actuator can be reduced.

As a result, the method realizes a robot device walking without a sensor, etc. with good balance on the unlevelled ground, thereby realizing a method of controlling a robot device with a simple entire configuration.

Furthermore, according to the present invention, the joint device includes a motor unit for generating the rotation torque for the actuator; and motor control means, provided in the motor unit, for controlling the drive of the motor unit.

As a result, the joint device can largely reduce the number of wires between the actuator and the external devices, thereby realizing a simple configuration of the joint device.

Furthermore, according to the present invention, the robot device includes a motor unit for generating the rotation torque for the actuator which drives a joint mechanism; and motor control means, provided in the motor unit, for controlling the drive of the motor unit.

As a result, the robot device can considerably reduce the number of wires connected to each actuator of a joint mechanism, thereby realizing a robot device with a simple configuration.

#### Brief Description of the Drawings

Fig. 1 is an oblique view of the configuration of the two-leg robot according to the embodiment of the present invention.

Fig. 2 is an oblique view of the configuration of the two-leg robot according to the embodiment of the present invention.

Fig. 3 shows the concept about the configuration of the two-leg robot according to the embodiment of the present invention.

Fig. 4 is a front view and a side view showing the configuration of the thigh joint mechanism.

Fig. 5 is a front view and an oblique view showing the configuration of the thigh joint mechanism.

Fig. 6 is a side view, a front view, and a side view showing the configuration of the ankle joint mechanism.

Fig. 7 is a block diagram showing the internal configuration of the two-leg walking robot shown in Fig. 1.

Fig. 8 is a block diagram showing the electrical connection between the sub-control unit and each motor.

Fig. 9 is a sectional view showing the configuration of each motor.

Fig. 10 shows the outline of the configuration of the rotor and the rotor axis magnetic pole angle sensor.

Fig. 11 is a partial sectional view showing the positional relationship between a rotor and a stator iron core.

Fig. 12 shows the outline of the configuration of a stator and a power substrate.

Fig. 13 shows the outline of the configuration of a torque amplification unit.

Fig. 14 shows the waveform for explanation of the magnetization pattern of a resin magnet of one-turn absolute angle sensor.

Fig. 15 shows the waveform for explanation of the first and the second one-turn absolute angle sensor signals.

Fig. 16 is a plan view showing the outline of the configuration of the control substrate.

Fig. 17 is a block diagram of the configuration of the control substrate.

Fig. 18 is a block diagram of the configuration of the power substrate.

Fig. 19 is a block diagram of the configuration of a one-chip microcomputer.

Fig. 20 is a block diagram showing the operations process of the CPU in the motor rotation control process mode.

Fig. 21 is a block diagram of the procedure of the rotor axis magnetic pole rotation number detecting process.

Fig. 22 is a flowchart showing the unlevelled ground walking control procedure.

Fig. 23 is a block diagram showing the connection relationship between each motor and the main control unit of the conventional robot.

#### Best Mode for Carrying Out the Invention

An embodiment of the present invention will be described below by referring to the attached drawings.

#### (1) Entire Configuration of the Robot according to the Embodiments

In Figs. 1 and 2, a robot 10 indicates a two-leg walking robot according to the embodiments. A head unit 12 is positioned above a belly unit 11. Arm units 13A and 13B are positioned as having the same configurations at each side of the belly unit 11. Leg units 14A and 14B are positioned as having the same configurations at each lower side of the belly unit 11.

The belly unit 11 is designed by connecting a frame 20 forming the upper portion of a trunk to a hip base 21 forming the

lower portion of the trunk through a knee joint mechanism 22. The upper portion of the trunk of the belly unit 11 can independent rotate, by driving motors M-1 and M-2 of the knee joint mechanism 22 fixed to the hip base 21 at the lower portion of the belly unit, on a roll axis 23 and a pitch axis 24 which are orthogonal to each other as shown in Fig. 3

The head unit 12 is mounted on the center of a shoulder base 25 fixed on the top of the frame 20 through a neck joint mechanism 26, and can independently rotate, by driving each of the motors M-3 and M-4 of the neck joint mechanism 26, on a pitch axis 27 and a yaw axis 28 which are orthogonal to each other as shown in Fig. 3.

Each of the arm units 13A and 13B is mounted on the left or the right of the shoulder base 25 through a shoulder joint mechanism 29, and can independently rotate, by driving each of the motors M-5 and M-6 of the shoulder joint mechanism 29, on a pitch axis 30 and a roll axis 31 which are orthogonal to each other as shown in Fig. 3.

In this case, in each of the arm units 13A and 13B, a motor M-8 forming each fore arm unit is connected to the output axis of a motor M-7 through an elbow joint mechanism 32, and a hand unit 33 is attached to the tip of the forearm.

In each of the arm units 13A and 13B, the forearm unit rotates on a yaw axis 34 shown in Fig. 3 by driving the motor M-7, and the forearm unit rotates on a pitch axis 35 shown in Fig. 3 by driving the motor M-8.

On the other hand, each of the leg units 14A and 14B is mounted to the hip base 21 below the belly unit through a thigh joint mechanism 36, and can independently rotate on a yaw axis 37, a roll axis 38 and a pitch axis 39 orthogonal to each other as shown in Fig. 3 by driving each of the motors M-9 through M-11 of the corresponding thigh joint mechanism 36.

In this case, in each of the leg units 14A and 14B, a frame 42 forming a lower leg unit is connected to the lower end of a frame 40 forming a thigh unit through a knee joint mechanism 41, and a foot unit 44 is connected to the lower end of the frame 42 through an ankle joint mechanism 43.

Thus, in each of the leg units 14A and 14B, the lower leg unit can rotate on a pitch axis 45 shown in Fig. 3 by driving a motor M-12 forming part of the knee joint mechanism 41, and the foot unit 44 can independently rotate on the pitch axis 45 and a roll axis 46 orthogonal to each other as shown in Fig. 3 by driving motors M-13 and M-14 of the ankle joint mechanism 43 respectively.

Figs. 4 and 5 show the configuration of the thigh joint mechanism 36 of the robot 10, and Fig. 6 shows the configuration of the ankle joint mechanism 43.

As shown in Figs. 4 and 5, the motor M-9 is fixed to the hip base 21 at the lower portion of the belly unit in the thigh joint mechanism 36. The output axis of the motor M-10 is connected to the output axis of the motor M-9 through a U-shaped connection

material 50, and a U-shaped material 51 is fixed to the side of the motor M-10.

In addition, a joint mechanism pulley 52 is connected to the U-shaped material 51 as freely rotating thereon, and the frame 40 forming part of the thigh unit in the leg units 14A and 14B is provided with one upper end of the U-shaped material 51 fixed to the joint mechanism pulley 52, and the other end attached to the U-shaped material 51 as freely rotating thereon.

The motor M-11 of the thigh joint mechanism 36 is fixed to the frame 40, and a pulley 53 attached to the output axis of the motor M-11 is connected to the joint mechanism pulley 52 through a timing belt 54.

Thus, in the thigh joint mechanism 36, the corresponding leg units 14A and 14B can independently rotate on the yaw axis 37, the roll axis 38, and the pitch axis 39 by driving each of the motors M-9 through M-11.

In this embodiment, the yaw axis 37 passing through the center of the output axis of the motor M-9 of the thigh joint mechanism 36, the roll axis 38 passing through the center of the output axis of the motor M-10, and the pitch axis 39 passing through the rotation center of the frame 40 are positioned such that they can cross at one point in the space.

In the ankle joint mechanism 43, as shown in Fig. 6, the output axis of the motor M-14 is fixed to a U-shaped connection material 60 fixed to the foot unit 44. A joint mechanism pulley

62 is fixed to the side of the motor M-14 through a U-shaped material 61.

The frame 42 forming part of the lower leg unit of the above described leg units 14A and 14B is mounted with one lower end connected to the center of the joint mechanism pulley 62 as freely rotating, and with the other lower end connected to the side of the U-shaped connection material 61 as freely rotating.

In addition, the motor M-13 is fixed to the frame 42, a pulley 63 is fixed to the output axis of the motor M-13, and the pulley 63 and the joint mechanism pulley 62 are connected with each other through a timing belt 64.

Thus, in the ankle joint mechanism 43, the foot unit 44 can independently rotate on the roll axis 45 and the pitch axis 46 by driving each of the motors M-13 and M-14.

On the other hand, in the robot 10, a control unit 72 is provided as storing in a box a main control unit 70 for controlling the entire operation of the robot 10, a peripheral circuit 71 such as a power supply circuit, a communications circuit, etc., a battery not shown in the attached drawings, and so forth on the back of the hip base 21 forming the lower part of the belly unit 11 as shown in Fig. 7.

The control unit 72 is connected to each of sub-control units 73A through 73D provided in each configuration unit (the belly unit 11, the head unit 12, each of the arm units 13A and 13B, and each of the leg units 14A and 14B) so that a necessary power

supply voltage can be provided for the sub-control units 73A through 73D and the control unit 72 can communicate with the sub-control units 73A through 73D.

In addition, the sub-control units 73A through 73D are connected in parallel to the motors M-1 through M-14 in the corresponding configuration unit as shown in Fig. 8 through two drive voltage supply cables 80, two control voltage supply cables 81, and one simultaneous clock supply cable 82, and are connected to each control substrate stored in each of the motors M-1 through M-14 in the daisy-chain system through two serial communications cables 83. Further, Fig. 8 shows the connection between the sub-control unit 74D in each of the leg units 14A and 14B and each of the motors M-9 through M-14.

At this time, the main control unit 70 stores, as the rotation angle of the output axis of each of the motors M-1 through M-14, the form in each state of the robot 10 such as 'standing state,' 'sitting state,' etc., and the forms in time series at predetermined time intervals (for example, 0.5 second to be hereinafter referred to as a first time interval) when the robot 10 is changing its state, and when the robot 10 performs a predetermined operation such as a walking operation, etc.

When the main control unit 70 makes the robot 10 change its state, perform an operation, etc., it switches in time series for each of the first time interval the rotation angle of the output axis of the motors M-1 through M-14 in each of the stored forms in

series, and then transmits the result to the corresponding sub-control units 74A through 74D.

On the other hand, each of the sub-control units 74A through 74D provides a power supply voltage for driving a motor and a control voltage for each of the corresponding motors M-1 through M-14 based on the power supply voltage supplied by the control unit 72 respectively through the drive voltage supply cable 80 and the control voltage supply cable 81.

Each of the sub-control units 74A through 74D computes the rotation angle, the rotation speed, or the rotation torque of each of the corresponding motors M-1 through M-14 at each timing (1 [ms] interval in this example) when the first time interval is equally divided into n (n is an integer equal to or larger than 2) from the rotation angle of each of the motors M-1 through M-14 assigned as described above at the first time interval from the main control unit 70, and controls each of the motors M-1 through M-14 based on the computation result.

As described above, in the robot 10, the drive of the motors M-1 through M-14 is controlled such that the form of the robot 10 being operated can sequentially match each of a time series of forms stored in the main control unit 70, and that various operations can be performed with predetermined movement or changed into various states.

(2) Configuration of Motors M-1 through M-14

(2-1) Entire configuration of motors M-1 through M-14

Described below is the configuration of each of the motors M-1 through M-14 used in the robot 10. Each of the motors M-1 through M-14 of the robot 10 comprises, as shown in Fig. 9, a motor unit 90 for generating the rotation torque, and a torque amplification unit 91 for amplifying the rotation torque generated by the motor unit 90 and outputting the amplified torque 91.

In this case, in the motor unit 90, a rotor axis 94 is provided and supported as freely rotating on rotation bearings 93A and 93B in a motor case 92. A rotor 97 is formed by designing the rotor axis 94 sharing the same axis with a rotor base unit 95, and a ring-shaped rotor magnet 96 magnetized to four poles as shown in Figs. 10(B) and 10(C).

In the motor case 92, as shown in Figs. 8 and 9A, six stator iron cores 98A through 98F are fixed at equal intervals ( $60^\circ$  intervals) as surrounding the rotor 97, and each of the stator iron cores 98A through 98F is wired to form coils 99A through 99F.

In the motor unit 90, two  $180^\circ$  opposing coils 99A and 99D, 99B and 99E, and 99C and 99F (three sets in all) are respectively set as a U phase, a V phase, and a W phase. The rotor 97 can be rotation-driven by applying to each of the coils 99A through 99F in the U phase, the V phase, and the W phase a drive current with the phase  $120^\circ$  shifted from each other, thereby generating the rotation torque.

On the other hand, the torque amplifier 91 has a gear case 100 fixed at the end of the motor case 92 as freely removable as

shown in Fig. 9 and Figs. 13A through 13C. The gear case 100 contains a circular internal gear 101, a sun gear 102 fixed at the end of the rotor axis 94, and a planet gear mechanism 104 comprising the first through the third planet gears 103A through 103C arranged at 120 [°] intervals between the internal gear 101 and the sun gear 102.

At this time, in the torque amplification unit 91, each of axes 105A through 105C of the first through the third planet gears 103A through 103C in the planet gear mechanism 104 is fixed to an output axis 106 arranged as freely rotating at the end of the gear case 100. With the configuration, the rotation torque provided from the motor unit 90 through the rotor axis 94 is transmitted to the output axis 106 through the planet gear mechanism 104, and then externally output through the output axis 106.

The torque amplification unit 91 also comprises a one-turn absolute angle sensor 109 comprising a circular resin magnet 107 fixed to the output axis 106, and the first and second hole elements 108A and 108B fixed to the surface of the gear case 100 such that they can face the surface of the resin magnet 107.

In this case, the resin magnet 107 is magnetized such that the magnetic flux density  $\phi(\theta_g)$  can be changed for two poles and a round as shown in Fig. 14, and is fixed to the output axis 106 as shown in Fig. 13(A). In addition, the first and second hole elements 108A and 108B are fixed to the surface of the gear case 100 with the phase difference of 90 [°] as shown in Fig. 13(B).

Thus, the one-turn absolute angle sensor 109 detects the rotation angle of the output axis 106 as a change of the magnetic flux density  $\phi$  ( $\theta_g$ ) at the arrangement position of the first and second hole elements 108A and 108B associated with the rotation of the output axis 106, and the detection result can be output as first and second one-turn absolute angle sensor signal S1A and S1B of a waveform provided by  $\sin(\theta_g)$  and  $\cos(\theta_g)$  as shown in Fig. 15 from the first and second hole elements 108A and 108B.

In addition to the above described configuration, the motor case 92 of the motor unit 90 contains the rotor axis magnetic pole angle sensor 100 for detecting the magnetic pole angle of the rotor axis 94, a control substrate 111 for controlling the rotation angle, the rotation speed, and the rotation torque, etc. of the output axis 94 according to the control command from the corresponding sub-control units 74A through 74D, and a power substrate 112 for supplying a drive current for each of the coils 99A through 99F of the motor unit 90 under the control of the control substrate 111.

A rotor axis magnetic pole angle sensor 110 comprises a resin magnet 113 fixed to the front end of the rotor base unit 95 of the rotor 97, and the first through fourth hole elements 114A through 114D mounted onto the control substrate 111. The resin magnet 113 is magnetized for the four poles as the rotor magnet 96 of the rotor 97 as shown in Figs. 10(B) and 10(C), and is fixed to the rotor base unit 95 with the same phase as the rotor magnet 96.

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The first through fourth hole elements 114A through 114D are mounted onto the control substrate 111 such that the first and second hole elements 114A and 114B face each other at  $180^\circ$  on the concentric circle with the rotor axis 94, and the third and fourth hole elements 114C and 114D are positioned with the phase shifted by  $45^\circ$  in the same direction as the first and the second hole elements 114A and 114B as shown in Fig. 16(B).

Thus, in the rotor axis rotation angle sensor 110, the magnetic pole angle of the rotor axis 94 can be detected as a change of the magnetic flux density with the arrangement of the first through fourth hole elements 114A through 114D associated with the rotation of the resin magnet 113 rotating with the rotor axis 94.

The magnetic pole angle of the rotor axis 94 refers to the angle obtained by multiplying the mechanical rotation angle of the rotor axis 94 by the half number of the magnetic poles of the rotor magnet 96. In this embodiment, since the rotor magnet 96 is magnetized for four poles, the magnetic angle ranges from 0 to  $2\pi$ .

On the other hand, the control substrate 111 is configured by loading a one-chip microcomputer 115 and a crystal oscillator 116 for generation of a CPU clock onto one side of a print wiring board, and by loading the first through fourth hole elements 114A through 114D of the above described rotor axis rotation angle sensor 110 and a temperature sensor 117 onto the other side as shown in Figs. 9, 10(A), 16, and 17.



rotation torque of the output axis 106 (Fig. 9) provided from the sub-control units 74A through 74D through the second cable 120 for 1 [ms]; the first and second 1-turn absolute angle sensor signals S1A and S1B; the first and second rotor axis magnetic pole angle sensor signals S2A and S2B; and first through third drive current detection signals S3A through S3C provided from the power substrate 112 as described later, and then outputs the computed first through third electric current command values to the power substrate 112 through a third cable 121.

The power substrate 112 is configured by mounting a plurality of power transistor chips 123 forming a coil drive block 122 shown in Fig. 18 on one side of the circular printed substrate as shown in Figs. 9, 12(B), and 12(C).

The coil drive block 122 rotation-drives the rotor 97 of the motor unit 90 by applying the drive current, whose level depends on the corresponding the first through third electric current command values, to each of the coils 99A through 99F in the U, V, and W phases of the motor unit 90 based on the first through third electric current command values provided from the one-chip microcomputer 115 of the control substrate 111.

At this time, the coil drive block 122 detects the level of the drive current applied to each of the coils 99A through 99F in the U, V, and W phases, and transmits the detection results to the control substrate 111 through the third cable 121 (Fig. 9) as the

first through third drive current detection signals S3A through S3C.

Thus, the motors M-1 through M-14 are designed to drive the motor unit 90 based on the specified rotation angle, the specified rotation speed, or the specified rotation torque provided from the sub-control units 74A through 74D through the control circuit comprising the one-chip microcomputer 115 of the control substrate 111 and the coil drive block 122 of the power substrate 112.

(2-2) Configurations of the one-chip microcomputer 115 and the coil drive block 122

The one-chip microcomputer 115 comprises, as shown in Fig. 19, an arithmetic operations block 128, a register 129, a rotor axis rotation angle detecting block 130, a torque-3-phase electric current signal converting block 131, an electric current controlling block 132, and first through fourth analog/digital conversion circuits 133 through 136.

The one-chip microcomputer 45 digital-converts in the first analog/digital conversion circuit 133 the first through third drive current detection signals S3A through S3C provided from the power substrate 112, and provides obtained first through third drive current detection data D3A and D3B for the electric current controlling block 132, and stores the first through third drive current detection data D3A and D3B in the register 129.

In addition, the one-chip microcomputer 115 digital-converts in a third analog/digital conversion circuit 135 the first and

second 1-turn absolute angle sensor signals S1A and S1B provided from the one-turn absolute angle sensor 109 (Figs. 9 and 13(C)), and stores the obtained first and second 1-turn absolute angle sensor data D1A and D1B in the register 129.

Furthermore, the one-chip microcomputer 115 digital-converts in a second analog/digital conversion circuit 134 the first and second rotor axis magnetic pole angle sensor signals S2A and S2B based on the output from the rotor axis magnetic pole angle sensor 110 provided from the first and second subtraction circuits 118A and 118B (Fig. 17), and inputs the obtained first and second rotor axis magnetic pole angle sensor data D2A and D2B to the rotor axis rotation angle detecting block 130.

The rotor axis rotation angle detecting block 130 detects a magnetic pole rotation angle (hereinafter referred to as a rotor axis magnetic pole rotation angle)  $P_{m1}$  of a rotor axis 24, and a magnetic pole angle  $\theta_p$  according to the provided first and second rotor axis magnetic pole angle sensor data D2A and D2B, stores the rotor axis rotation angle  $P_{m1}$  in the register 129, and transmits the magnetic pole angle  $\theta_p$  to the torque-3-phase electric current signal converting block 131.

The magnetic pole rotation angle of the rotor axis 94 (rotor axis magnetic pole rotation angle  $P_{m1}$ ) refers to the angle at which a change in the magnetic poles in a pair of the adjacent N and S poles of the resin magnet 113 detected by the first through fourth hole elements 114A through 114D with the rotation of the rotor

axis 94 can be defined as one cycle (0 through  $2\pi$ ). Since the resin magnet 113 is magnetized for four poles in the present embodiment, the rotor axis magnetic pole rotation angle  $P_{m1}$  ranges from 0 to  $4\pi$ .

The arithmetic operations block 128 obtains a target rotation torque  $T_0$  according to the first and second 1-turn absolute angle sensor data D1A and D1B and the rotor axis magnetic pole rotation angle  $P_{m1}$  stored in the register 129, and the specified rotation angle, the specified rotation speed, or the specified rotation torque provided from the sub-control unit, and stores the operations result in the register 129. The target rotation torque  $T_0$  is computed for 1 [ms] provided the specified rotation angle, the specified rotation speed, or the specified rotation torque from the sub-control unit.

The target torque  $T_0$  is read from the register 129 one after another by the torque-3-phase electric current signal converting block 131. The torque-3-phase electric current signal converting block 131 computes the above described first through third electric current command values  $U_r$ ,  $V_r$ , and  $W_r$  indicating the values of drive currents to be applied to each of the coils 99A through 99F in the U, V, and W phases in the motor unit 90 based on the target torque  $T_0$ , and the magnetic pole angle  $\theta_p$  of the rotor axis 94 provided from the rotor axis rotation angle detecting block 130, and transmits the computation results to the electric current controlling block 132.

The electric current controlling block 132 performs a predetermined signal process containing a compensating process for a voltage change on the first through third electric current command values  $U_r$ ,  $V_r$ , and  $W_r$  based on the first through third electric current command values  $U_r$ ,  $V_r$ , and  $W_r$  provided from the torque-3-phase electric current signal converting block 131, and the first through third drive current detection data D3A through D3C provided from the first analog/digital conversion circuit 133. Then, the electric current controlling block 132 PWM (Pulse Width Modulation) modulates the result, and transmits the obtained first through third PWM signals S4A through S4C to the coil drive block 121 of the power substrate 112 through the third cable 121.

The third cable 121 is provided with two lines for each of the first through third PWM signals S4A through S4C. When the output axis 106 (Fig. 9) is driven for normal rotation, the electric current controlling block 132 transmits the first through third PWM signals S4A through S4C to the coil drive block 122 of the power substrate 112 through a first line, and transmits logic '0' level signals (hereinafter referred to as first through third reference signals) S5A through S5C in the first through third PWM signals S4A through S4C to the coil drive block 122 of the power substrate 112 through a second line.

When the output axis 106 is driven for inverse rotation, the electric current controlling block 132 transmits the first through third PWM signals S4A through S4C to the coil drive block 122 of



between the central point of the connection between the collector of the first PNP-type transistor TR1 and the collector of the first NPN-type transistor TR3 in the first through third inverter circuits 140A through 140C, and the central point of the connection between the collector of the second PNP-type transistor TR2 and the second NPN-type transistor TR4.

In the coil drive block 122, the first through third PWM signals S4A through S4C provided through the first or the second line are converted into drive currents  $I_u$ ,  $I_v$ , and  $I_w$  in an analog waveform in the corresponding first through third inverter circuits 140A through 140C for each of the U, V, and W phases, and are applied to respective coils 99A through 99F in the corresponding U, V, and W phases.

In the coil drive block 122, the levels of the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  provided for the coils 99A through 99F in the U, V, and W phases are detected by an electric current sensor 141 comprising the coils provided in the first through third inverter circuits 140A through 140C, and the detection result is transmitted to the first analog/digital conversion circuit 133 (Fig. 19) of the one-chip microcomputer 115 of the control substrate 111 as the above described first through third drive current detection signals S3A through S3C.

The detailed configuration of the arithmetic operations block 128 is described below by referring to Fig. 19.

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The arithmetic operations block 128 comprises a CPU (Central Processing Unit) 148, a ROM (Read Only Memory) 149 storing various programs, a RAM (Random Access Memory) 150 as the work memory of the CPU 148, a serial communications input/output circuit 152 which is an input/output interface circuit to and from the corresponding sub-control units 73A through 73D, a servo-interruption signal generation circuit 153 for generating a servo-interruption signal S10 of a 1 [ms] cycle for servo-interruption and a PWM pulse signal S11 of a 50 [ $\mu$ m] cycle which is a PWM cycle, and a watch dog signal generation circuit 154 for generating a watch dog signal S12 having a predetermined cycle longer than 1 [ms] cycle for the CPU 148 detecting whether the servo-interruption signal S10 is correctly generated from the servo-interruption signal generation circuit 153. These components are interconnected through a CPU bus 155.

When a control voltage (5 [V]) is supplied by the corresponding sub-control units 73A through 73D, the CPU 148 first performs the initial processes for various initial values, parameter settings, etc. on the serial communications input/output circuit 152, the counter timer control circuit 153, the rotor axis rotation angle detecting block 130, the torque-3-phase electric current signal converting block 131, the electric current controlling block 132, etc. based on the initial program stored in the ROM 149.

Furthermore, based on the servo-interruption signal S10 provided from the counter timer control circuit 153 obtained as a result of the above described processes, and the corresponding program stored in the ROM 149, the CPU 148 executes a motor rotation control operations process for generating the above described target rotation torque  $T_0$ , a serial communications control process to and from the corresponding sub-control units 73A through 73D on a 1 [ms] cycle in a time-divisional manner.

(2-3) Software process

In the arithmetic operations block 128, the CPU 148 executes the motor rotation control operations process, the serial communications control process, etc. on 1[ms] cycle in a time-divisional manner based on the servo-interruption signal S10 provided from the counter timer control circuit 153, and the corresponding program stored in the ROM 149. Described below is the process of the CPU 148 in the process mode for the above described operations.

(2-3-1) Process of the CPU 148 in the motor rotation control operations process mode

The process of the CPU 148 in the motor rotation control operations mode is performed to compute the target rotation torque  $T_0$  according to the designation of the value of the specified rotation position, the specified rotation speed, or the specified rotation torque assigned for 1[ms] by the above described corresponding sub-control units 73A through 73D.

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The CPU 148 computes the target rotation torque  $T_0$  by computing the rotation position  $P_m$  of the output axis 94 (Fig. 9) based on the rotor axis magnetic pole rotation angle  $P_{m1}$  stored in the register 129 by the rotor axis rotation angle detecting block 130 when the specified rotation position  $P_{ref}$  is provided from the corresponding sub-control units 73A through 73D, by computing the target rotation speed  $V_{mref}$  for the specified rotation position  $P_{ref}$  and the current rotation speed  $V_m$  of the output axis by computing the rotations using the rotation position  $P_m$  by the following Equations (1), and (2), and then by performing the following Equation (3) based on the above described Equations.

$$V_{mref} = (P_{ref} - P_m) \times K_{pp} \quad \dots (1)$$

$$V_m = P_m \times S \quad \dots (2)$$

$$T_0 = \left\{ [V_{mref} - V_m] \times \left[ 1 + \frac{K_{vi}}{S} \right] \right\} \times K_{vp} \quad \dots (3)$$

When the specified rotation speed  $V_{ref}$  is provided from the sub-control units 73A through 73D, the current rotation speed  $V_m$  of the output axis 94 is computed by the Equation (2), and the target rotation torque  $T_0$  is computed by performing the operation by the following Equation (4) based on the rotation speed  $V_m$ .

$$T_0 = \left\{ [V_{ref} - V_m] \times \left[ 1 + \frac{K_{vi}}{S} \right] \right\} \times K_{vp} \quad \dots (4)$$

When the specified rotation torque  $T_{ref}$  is provided from the sub-control units 73A through 73D, it is used as is as the target rotation torque  $T_0$ .

In these Equations (1) through (4),  $S$  indicates a Laplace operator,  $K_{pp}$ ,  $K_{vi}$ , and  $K_{vp}$  indicates control gain parameters set by the sub-control unit. By changing the values of the control gain parameters  $K_{pp}$ ,  $K_{vi}$ , and  $K_{vp}$ , the answers of the motors M-1 through M-14 in response to the specified rotation angle  $P_{ref}$  and the specified rotation speed  $V_{ref}$  can be changed.

Fig. 20 shows the practical process procedure of the CPU 148 in the motor rotation control operations process mode.

The CPU 148 computes the number of magnetic pole rotations (hereinafter referred to as the number of rotor axis magnetic pole rotations)  $N_m$  of the rotor axis 94 based on the first and second absolute angle sensor data D1A and D1B stored in the register 129 when the specified rotation angle  $P_{ref}$  is provided from the sub-control units 73A through 73D (step SP1).

The number of rotor axis magnetic pole rotations  $N_m$  is defined as the number of rotations each indicating a change of a magnetic flux at a pair of adjacent N and S poles of the resin magnet 113 detected by the first through fourth hole elements 114A through 114D of the rotor axis magnetic pole angle sensor 110 with the rotation of the rotor axis 94. According to the embodiment, since

the resin magnet 113 is magnetized for four magnetic poles, the number of rotor axis magnetic pole rotations  $N_m$  is 2 when the rotor axis 94 mechanically makes one turn.

Then, the number of rotor axis magnetic pole rotations  $N_m$  can be obtained as follows. First, the phase  $\theta_g$  of the first and second 1-turn absolute angle sensor signals S1A and S1B respectively represented by  $\sin \theta_g$  and  $\cos \theta_g$  is computed according to the rotor axis magnetic pole rotation number detecting procedure shown in Fig. 21 in the software process based on the first and second absolute angle sensor data D1A and D1B stored in the register 41 (step SP1A). The phase  $\theta_g$  is multiplied by the gear ratio  $N$  of a planet gear mechanism unit 16 of a torque amplification unit 3 (step SP1B). The multiplication result is divided by  $2\pi$ , and the integer portion of the division result is multiplied by a half value  $N_p$  of the number of magnetic poles (4 according to the present embodiment) of the resin magnet 113 of the rotor axis magnetic pole angle sensor 110 (Fig. 9) (step SP1C).

In addition, the CPU 148 computes the rotation angle  $P_m$  of the output axis 106 by performing the operation by the following Equation (6) using the  $P_{m0}$  obtained by the following Equation (5) as an initial value based on the number of rotor axis magnetic pole rotations  $N_m$  computed as described above and the rotor axis magnetic pole rotation angle data  $P_{m1}$  stored in the register 129 as shown in Fig. 20 (step SP2).

$$Pm0 = 2\pi \times Nm \quad \dots (5)$$

$$Pm = Pm0 \times Pm1 \quad \dots (6)$$

Then, the CPU 148 detects the error  $P_e$  (hereinafter referred to as a rotation angle error) for the specified rotation angle  $P_{ref}$  (step SP3) by subtracting this rotation angle  $P_m$  from the specified rotation angle  $P_{ref}$ .

Then, the CPU 148 computes the target rotation angle  $V_{mref}$  for the specified rotation angle  $P_{ref}$  by multiplying the rotation angle error  $P_e$  by the proportion gain parameter  $K_{pp}$  (step SP4).

The CPU 148 then computes the rotation speed  $V_m$  of the output axis 106 by differentiating the rotor axis magnetic pole rotation angle  $P_{m1}$  stored in the register 129 (step SP5), and computes the speed error  $Ve$  by subtracting the rotation speed  $V_m$  computed in step SP5 from the target rotation speed  $V_{mref}$  computed in step SP4 (step SP6).

Then, the CPU 148 sequentially multiplies the speed error  $Ve$  by the speed integration gain obtained by the following Equation (7) and the proportion gain  $K_{vp}$  (step SP7 and step SP8).

$$\frac{S + K_{vi}}{S} \quad \dots (7)$$

Thus, the target rotation torque  $T_0$  can be obtained.

When the rotation speed  $V_{ref}$  is provided from the sub-control units 73A through 73D in the motor rotation control operation process mode, the CPU 148 starts the process from the step SP6. When the specified rotation torque  $T_{ref}$  is provided, it is stored in the register 129 as the target rotation torque  $T_0$ .

(2-3-2) Process of CPU 148 in the serial communications process mode

The CPU 148 communicates with the sub-control units 73A through 73D in the serial communication process mode, inputs a control command and a change parameter from the sub-control units 73A through 73D, or transmits the internal monitor signal to the sub-control units 73A through 73D.

(2-4) Relationship between coil drive current and output torque

Described below is the relationship between the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  to be applied to each of the coils 99A through 99F in the U, V, and W phases of the motor unit 90 in the motors M-1 through M-14 with the above described configuration, and the rotation torque (hereinafter referred to as an output torque) to be externally output through the output axis 106.

When the density of the crossing magnetic fluxes of each of the coils 99A through 99F in the U, V, and W phases obtained when the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  are applied to each of the coils 99A through 99F in the U, V, and W phases is defined as  $\phi_u$ ,  $\phi_v$ , and  $\phi_w$ , the output torque  $T$  ( $\theta_p$ ) is obtained by the following

Equation (8) using the magnetic pole angle  $\theta_p$  of the rotor axis 94 of the motor unit 90.

$$T(\theta_p) = I_u \times \phi_u \times K_0 + I_v \times \phi_v \times K_0 + I_w \times \phi_w \times K_0 \quad \dots (8)$$

In the Equation (8) above,  $K_0$  indicates a constant coefficient obtained when the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  are applied to each of the coils 99A through 99F.

The drive currents  $I_u$ ,  $I_v$ , and  $I_w$  to be applied to each of the coils 99A through 99F in the U, V, and W phases are controlled as shown by the following Equations (9), (10), and (11).

$$I_u = I_0 \times \sin \theta_p \quad \dots (9)$$

$$I_v = I_0 \times \sin \left[ \theta_p + \frac{2\pi}{3} \right] \quad \dots (10)$$

$$I_w = I_0 \times \sin \left[ \theta_p - \frac{2\pi}{3} \right] \quad \dots (11)$$

Each of the magnetic flux density  $\phi_u$ ,  $\phi_v$ , and  $\phi_w$  is computed as follows.

$$\phi_u = \phi_0 \times \sin \theta_p \quad \dots (12)$$

$$\phi_v = \phi_0 \times \sin\left[\theta_p + \frac{2\pi}{3}\right] \quad \dots (13)$$

$$\phi_w = \phi_0 \times \sin\left[\theta_p - \frac{2\pi}{3}\right] \quad \dots (14)$$

Accordingly, the output torque  $T(\theta_p)$  is obtained by substituting the Equations (9) through (14) in the Equation (8) as represented by the following Equation (15).

$$\begin{aligned} T(\theta_p) &= I_0 \times \phi_0 \times K_0 \left\{ \sin \theta_p \times \sin \theta_p \right. \\ &\quad + \sin\left[\theta_p + \frac{2\pi}{3}\right] \times \sin\left[\theta_p + \frac{2\pi}{3}\right] \\ &\quad \left. + \sin\left[\theta_p - \frac{2\pi}{3}\right] \times \sin\left[\theta_p - \frac{2\pi}{3}\right] \right\} \quad \dots (15) \\ &= I_0 \times \phi_0 \times K_1 \quad (\text{where, } K_1 = 1.5K_0) \end{aligned}$$

Therefore, in the motors M-1 through M-14, an output torque proportional to the level of the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  to be applied to each of the coils 99A through 99F can be obtained.

### (3) Unleveled Ground Walking Control Process

In addition to the above described configuration, the sub-control unit 73D of each of the leg units 14A and 14B of the robot 10 is designed to perform an unleveled ground walking control process for controlling each of the motors M-13 and M-14 of the

ankle joint mechanism 43 such that the robot 10 can correctly walk while keeping balance even on the unlevelled ground.

In this case, the unlevelled ground walking control process can be performed by controlling the rotation of each of the motors M-13 and M-14 of the ankle joint mechanism 43 to allow the reverse surface of the foot unit 44 on the walkway to follow the tilt or the convexity/concavity surface of the walkway (control the tilt of the foot unit based on the tilt or the convexity/concavity of the walkway). The control can be performed by controlling the rotation of each of the motors M-13 and M-14 such that the external force applied to the output axis 106 (Fig. 9) of each of the motors M-13 and M-14 of the ankle joint mechanism 43 can be constantly '0.'

In the sub-control unit 73D of each of the leg units 14A and 14B, the above described unlevelled ground walking control is performed on each of the motors M-13 and M-14 of the ankle joint mechanism 43 in the unlevelled ground walking controlling procedure RT1 shown in Fig. 22 each time a target rotation angle of each of the motors M-9 through M14 is provided from the main control unit 70 (Fig. 7) at the first time intervals in the walking operation.

That is, when the main control unit 70 provides a target rotation angle of each of the motors M-13 and M-14 of the ankle joint mechanism 43 for the sub-control unit 73D of each of the leg units 14A and 14B, the sub-control unit 73D starts the unlevelled ground walking controlling procedure RT1 in step SP10, and then,

in step SP11, computes the specified rotation angle, the specified rotation speed, or the specified rotation torque of each of the motors M-13 and M-14 for 1 [ms] which is a control cycle of each of the motors M-13 and M-14 based on the target rotation angle of each of the motors M-13 and M-14 of the ankle joint mechanism 43 preliminarily provided by the main control unit 70, and the target rotation angle of each of the motors M-13 and M-14 newly provided by the main control unit 70.

Accordingly, when a target rotation angle of each of the motors M-13 and M-14 is provided from the main control unit 70 to the sub-control unit 73D every 0.5 second, the specified rotation angle, the specified rotation speed, or the specified rotation torque of each of the motors M-13 and M-14 for 1 [ms] is computed 50 times in time series.

In step SP11, the sub-control unit 73D resets to '0' the count value indicating the order (that is, the order of the specified rotation angle, the specified rotation speed, or the specified rotation torque in the 50 time series data) of the specified rotation angle, the specified rotation speed, or the specified rotation torque being counted in an internal counter.

Then, in step SP12, the sub-control unit 73D increases the count value of the internal counter by 1. Then, control is passed to step SP13, and the specified rotation angle, the specified rotation speed, or the specified rotation torque corresponding to

the count value is transmitted to each of the motors M-13 and M-14 of the ankle joint mechanism 43.

At this time, the first through third drive current detection data D3A through D3C (Fig. 19) obtained by digital-converting the first through third drive current detection signals S3A through S3C (Fig. 18) output from the electric current sensor 71 (Fig. 18) of each of the coil drive blocks 140A through 140C (Fig. 18) of the power substrate 112 (Fig. 18) in the first analog/digital conversion circuit 133 of the one-chip microcomputer 115 (Fig. 19) is provided from the motors M-13 and M-14 to the sub-control unit 73D through the communications with each of the motors M-13 and M-14 of the ankle joint mechanism 43.

Thus, the sub-control unit 73D fetches the first through third drive current detection data D3A through D3C from each of the motors M-13 and M-14 in step SP14, then computes the output torque  $T_m$  of each of the motors M-13 and M-14 of the ankle joint mechanism 43 based on the first through third drive current detection data D3A through D3C in step SP15.

Furthermore, in step SP16, the sub-control unit 73D computes the torque (hereinafter referred to as an external force torque  $T_f$ ) generated on the output axis 106 of each of the motors M-13 and M-14 by an external force by subtracting the preliminarily stored torque  $T_g$  generated by their weights when they are formed on the output axis 106 of each of the motors M-13 and M-14 from the output torque  $T_m$ .

In addition, in step SP17, the sub-control unit 73D determines for each of the motors M-13 and M-14 whether or not the computed value of the external force torque  $T_f$  is '0.'

Obtaining an affirmative result in step SP17 indicates, for example, the foot unit 44 does not touch the ground or the reverse surface of the foot unit 44 touches the ground as following the tilt or the concavity/convexity of the walkway. At this time, the sub-control unit 74D returns to step SP12, and performs the processes in and after step SP2 for 1 [ms].

On the other hand, obtaining a negative result in step SP17 indicates that the reverse surface of the foot unit 44 touches the ground as not following the tilt or the concavity/convexity of the walkway. At this time, the sub-control unit 74D amends the next specified rotation angle, the specified rotation speed, or the specified rotation torque to be supplied for each of the motors M-13 and M-14 in step SP18 such that the value of the external force torque  $T_f$  provided for the output axis 108 of the motors M-13 and M-14 can reach '0,' then returns to step SP12, and then performs the processes in and after step SP2 for 1 [ms].

Thus, the robot 10 can correctly walk while keeping good balance even on the unlevelled ground by the sub-control unit 73D of each of the leg units 14A and 14B amending the specified rotation angle, the specified rotation speed, or the specified rotation torque to be supplied for the motors M-13 and M-14 of the ankle joint mechanism 43 as necessary.

(4) Operation and Effect of the Present Embodiment

With the above described configuration, when the robot 10 is walking, the rotation of the motors M-13 and M-14 is controlled such that the external force torque  $T_f$  applied to the output axis 106 of each of the motors M-13 and M-14 of the ankle joint mechanism 43 of each of the leg units 14A and 14B can be constantly '0.'

Therefore, with this robot 10, the reverse surface of the foot unit 44 can follow even the unlevelled ground having tilt and convexity/concavity, thereby realizing a walk with good balance. Thus, the robot 10 can omit various sensors for the conventional unlevelled ground walking control.

In addition, since the robot 10 contains the control substrate 111 and the power substrate 112 for drive-controlling the motor unit 90 in each of the motors M-1 through M-14, all motors M-1 through M-14 can be connected to each of the sub-control units 73A through 73D through a total of 7 cables as shown in Fig. 8, thereby reducing the number of wires connected to the entire robot.

Furthermore, since the robot 10 has the configuration shown in Fig. 9 in which the motor unit 90 and the torque amplification unit 91 are stored as compactly incorporated as each of the motors M-1 through M-14, the configuration of each joint mechanism (the waist joint mechanism 22, the neck joint mechanism 26, the shoulder joint mechanism 29, the elbow joint mechanism 32, the

thigh joint mechanism 36, the knee joint mechanism 41, and the ankle joint mechanism 43) can be simpler than the configuration in which the motor unit 90 and the torque amplification unit 91 are mounted independent of each other, thereby realizing a small joint mechanism (and the robot 10).

With the above described configuration, the two-leg walking robot 10 can follow even the unlevelled ground having tilt and convexity/concavity by controlling the rotation of the motors M-13 and M-14 such that the external force torque  $T_g$  applied to the output axis 106 of each of the motors M-13 and M-14 of the ankle joint mechanism 43 of each of the leg units 14A and 14B can be constantly '0' in the walking operation, thereby realizing a walk with good balance. Thus, various sensors used in the conventional unlevelled ground walking control can be omitted, thereby realizing a robot having a simple configuration.

In addition, since the robot 10 contains the control substrate 111 and the power substrate 112 for drive-controlling the motor unit 90 in the motors M-1 through M-14, thereby reducing the number of wires in the entire robot and realizing a robot having a simpler configuration.

#### (5) Other Embodiments

According to the above described embodiments, the present invention is applied to a two-leg walking robot 10. However, the present invention is not limited to this application, but can be widely applied to various robots. In this case, the invention

relating to the control of a joint mechanism can be widely applied to a four-leg walking robot and other robots with the number of legs other than two or four. In addition, the invention including a motor control unit as a drive unit for each of the joint mechanism in a motor unit can also be widely applied to various robots other than walking robots.

In the above described embodiments, the invention relating to the control of a joint mechanism is applied to the ankle joint mechanism 43 connecting the lower leg unit as the first link (first component) of the leg units 14A and 14B to the foot unit 44 as the second link (second component). However, the present invention is not limited to this application, but can be widely applied to various units other than the ankle joint mechanism 43, for example, to a wrist joint, etc.

Furthermore, in the above described embodiments, the electric current sensor 71 is made of the coil mounted as shown in Fig. 18 as an electric current detection unit for detecting the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  (shown in Fig. 18) of the motors M-1 through M-14. However, the present invention is not limited to this application, but can be widely applied to various configurations depending on the configuration of the applicable actuator.

In addition, according to the above described embodiments, the function of an external torque detection unit for detecting the external torque (external force torque  $T_f$ ) applied to the

output axis 106 of the motors M-13 and M-14 based on the drive currents  $I_u$ ,  $I_v$ , and  $I_w$  (Fig. 18) of the motors M-13 and M-14 detected by the electric current sensor 71 (Fig. 18) is assigned to the sub-control unit 73D of each of the leg units 14A and 14B. However, the present invention is not limited to this application, but the function can be assigned to the arithmetic operations block 128 (Fig. 19) in the motors M-13 and M-14.

Furthermore, according to the above described embodiment, the control substrate 111 and the power substrate 122 are configured as shown in Figs. 17 through 21 as motor control units for drive-controlling the motor unit 90 of each of the motors M-1 through M-14 configured as shown in Fig. 9. However, the present invention is not limited to this application, but various configurations can be widely applied.

#### Industrial Applicability

The present invention can be applied to a two-leg walking robot or other walking robots.

## Claims

1. A joint mechanism control apparatus having an actuator for generating a rotation torque whose level depends on a drive current, connecting a first link to a second link as freely rotating on an predetermined axis, and rotating the first link on the predetermined axis based on the rotation torque output from the actuator through an output axis of the actuator, characterized by comprising:

electric current detection means for detecting an electric current value of the drive current of the actuator; and

external force torque detection means for detecting a level of a torque by an external force applied to the output axis of the actuator based on the electric current value detected by said electric current detection means.

2. The joint mechanism control apparatus according to Claim 1, characterized by further comprising:

control means for controlling the actuator based on a detection result from said external force torque detection unit such that the external force applied to the output axis of the actuator can be removed.

3. The joint mechanism control apparatus according to Claim 1, characterized in that:

said actuator comprises:

a motor unit generating the rotation torque depending on a supplied drive current;

a torque amplification unit amplifying the rotation torque generated by said motor unit, and transmits the torque to said output axis; and

motor control means for controlling said motor unit by supplying said motor unit with the drive current at a level according to externally provided control information, and

said motor control unit is provided in said motor unit.

4. A joint mechanism control method having an actuator for generating a rotation torque whose level depends on a drive current, connecting a first link to a second link as freely rotating on an predetermined axis, and rotating the first link on the predetermined axis based on the rotation torque output from the actuator through an output axis of the actuator, characterized by comprising:

a first step of detecting an electric current value of the drive current of the actuator; and

a second step of detecting a level of torque by an external force applied to the output axis of the actuator based on the detected electric current value.

5. The joint mechanism control method according to Claim 4, characterized by further comprising:

a third step of controlling the actuator such that the torque by the external force applied to the output axis of the actuator can be removed based on a detected result obtained in said second step.

6. A robot device including a joint mechanism having an actuator for generating a rotation torque whose level depends on a drive current, connecting a first component to a second component as freely rotating on a predetermined axis, and rotating the first component on the predetermined axis based on the rotation torque output from the actuator through an output axis of the actuator, characterized by comprising:

electric current detection means for detecting an electric current value of the drive current of the actuator; and

external force torque detection means for detecting a level of a torque by an external force applied to the output axis of the actuator based on the electric current value detected by said electric current detection means.

7. The robot device according to Claim 6, characterized by further comprising:

control means for controlling said actuator such that the torque by the external force applied to the output axis of the

actuator can be removed based on a detected result obtained in said external force torque detection means.

8. The robot device according to Claim 6, characterized in that :

said actuator comprises:

a motor unit generating the rotation torque depending on a supplied drive current;

a torque amplification unit amplifying the rotation torque generated by said motor unit, and transmits the torque to said output axis; and

motor control means for controlling said motor unit by supplying said motor unit with the drive current at a level according to externally provided control information, and

said motor control means is provided in said motor unit.

9. A robot device control method having a joint mechanism including an actuator for generating a rotation torque whose level depends on a drive current, connecting a first component to a second component as freely rotating on an predetermined axis, and rotating the first component on the predetermined axis based on the rotation torque output from the actuator through an output axis of the actuator, comprising:

a first step of detecting an electric current value of the drive current of the actuator; and

a second step of detecting a level of a torque by an external force applied to the output axis of the actuator based on the detected electric current value.

10. The robot device control method according to Claim 10, characterized in that:

a third step of controlling the actuator such that the torque by the external force applied to the output axis of the actuator can be removed based on a detected result obtained in said second step.

11. A robot device having a pair of leg units in each of which a lower leg unit is connected to a thigh unit through a knee joint mechanism, and a foot unit is connected to the lower leg unit through an ankle joint mechanism, said foot units of said leg units are alternately touch a walking path such that a walking operation can be performed with the leg units are driven in a predetermined pattern, characterized by comprising:

an actuator, provided in said ankle joint mechanism, generating a rotation torque whose level depends on a drive current for rotation-driving said foot unit on a predetermined axis;

electric current detection means for detecting an electric current value of the drive current of the actuator; and

external force torque detection means for detecting a level of a torque by an external force applied to the output axis of the actuator based on the electric current value detected by said electric current detection means; and

control means for controlling the actuator based on a detection result from said external force torque detection unit such that the external force applied to the output axis of the actuator can be removed.

12. The robot device according to Claim 11, characterized in that:

said actuator comprises:

a motor unit generating the rotation torque depending on a supplied drive current;

a torque amplification unit amplifying the rotation torque generated by said motor unit, and transmits the torque to said output axis; and

motor control means for controlling said motor unit by supplying said motor unit with the drive current at a level according to externally provided control information, and

said motor control means is provided in said motor unit.

13. A method of controlling a robot device having a pair of leg units in each of which a lower leg unit is connected to a thigh unit through a knee joint mechanism, and a foot unit is connected

to the lower leg unit through an ankle joint mechanism, said foot units of said leg units are alternately touch a walking path such that a walking operation can be performed with the leg units are driven in a predetermined pattern, characterized by comprising:

a first step of detecting an electric current value of the drive current provided for an actuator, provided in said ankle joint mechanism, generating a rotation torque whose level depends on a drive current for rotation-driving said foot unit on a predetermined axis;

a second step of detecting a level of a torque by an external force applied to the output axis of the actuator based on the detected electric current value; and

a third step of controlling the actuator, based on a detection result obtained in said second step, such that the external force applied to the output axis of the actuator can be removed.

14. A joint device in which a first link is connected to a second link as freely rotating on a predetermined axis, comprising

an actuator generating rotation torque for rotation-driving said first link on said predetermined axis, characterized in that said actuator comprises:

a motor unit generating the rotation torque; and

motor control means for controlling the drive of said motor unit; and

said motor control means is provided in said motor unit.

15. The joint device according to Claim 14, further comprising:

torque amplification means for amplifying the rotation torque output from said motor unit, characterized in that

said motor unit and said torque amplification means are incorporated into one unit.

16. A robot device having a joint mechanism in which a first component is connected to a second component as freely rotating on a predetermined axis, comprising:

an actuator generating a rotation torque for rotation-drive said first component on the predetermined axis, wherein

said actuator comprises:

a motor unit generating the rotation torque; and

motor control means for controlling the drive of said motor unit characterized in that

said motor control means is provided in said motor unit.

17. The robot device according to Claim 16, further comprising

a torque amplification means for amplifying the rotation torque output from said motor unit, characterized in that

said motor unit and said torque amplification means are incorporated into one unit.

## ABSTRACT

A joint mechanism control device and method, and a robot device and its control method include: electric current detection means for detecting an electric current value of the drive current applied to an actuator for driving a joint mechanism; and external force torque detection means for detecting the level of the torque by an external force applied to the output axis of the actuator based on the electric current value detected by the electric current detection means. In addition, a joint device and the robot device include: motor unit for generating the rotation torque for the actuator; and motor control means, provided in the motor unit, for controlling the drive of the motor unit.

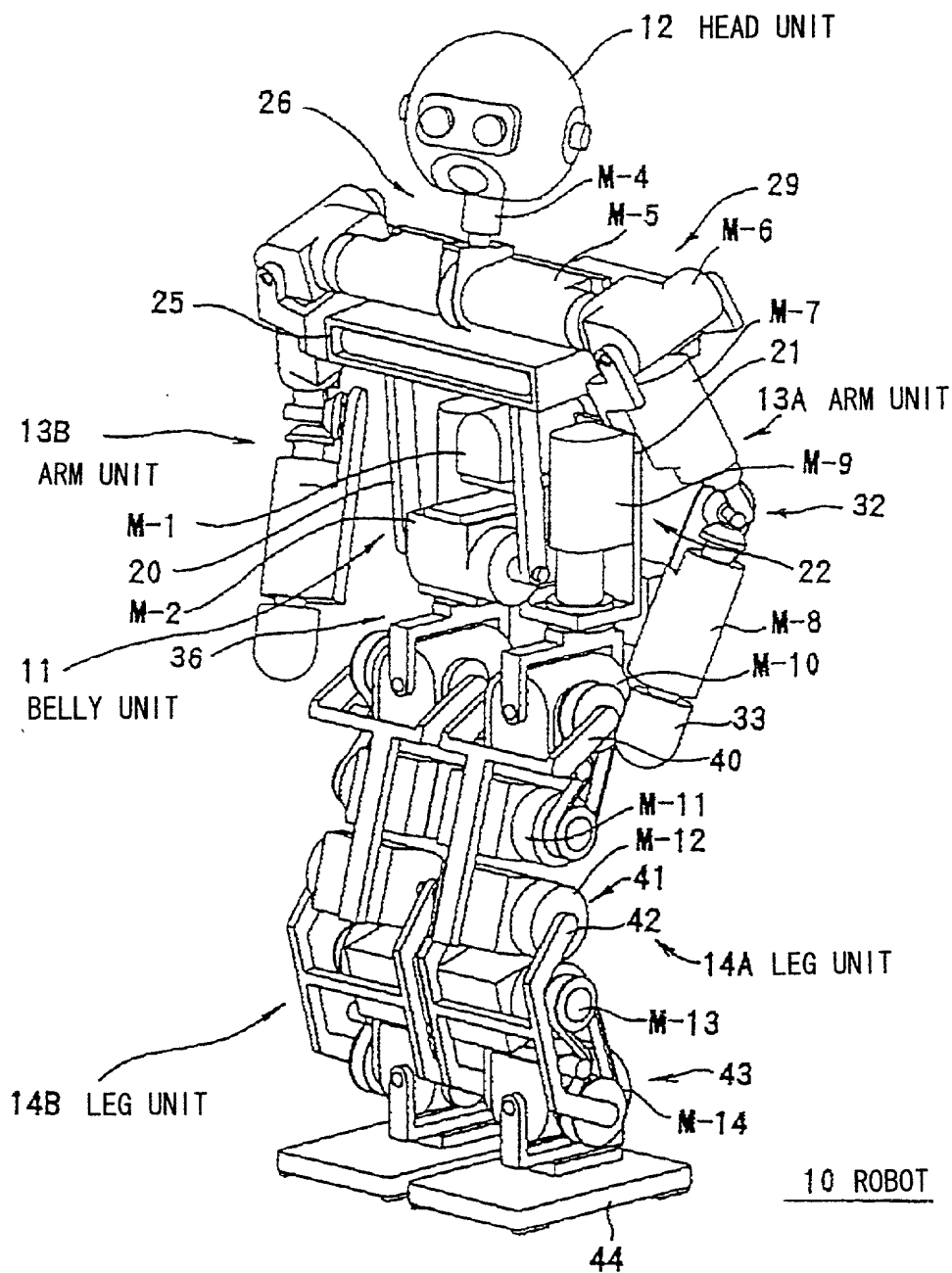


FIG. 1

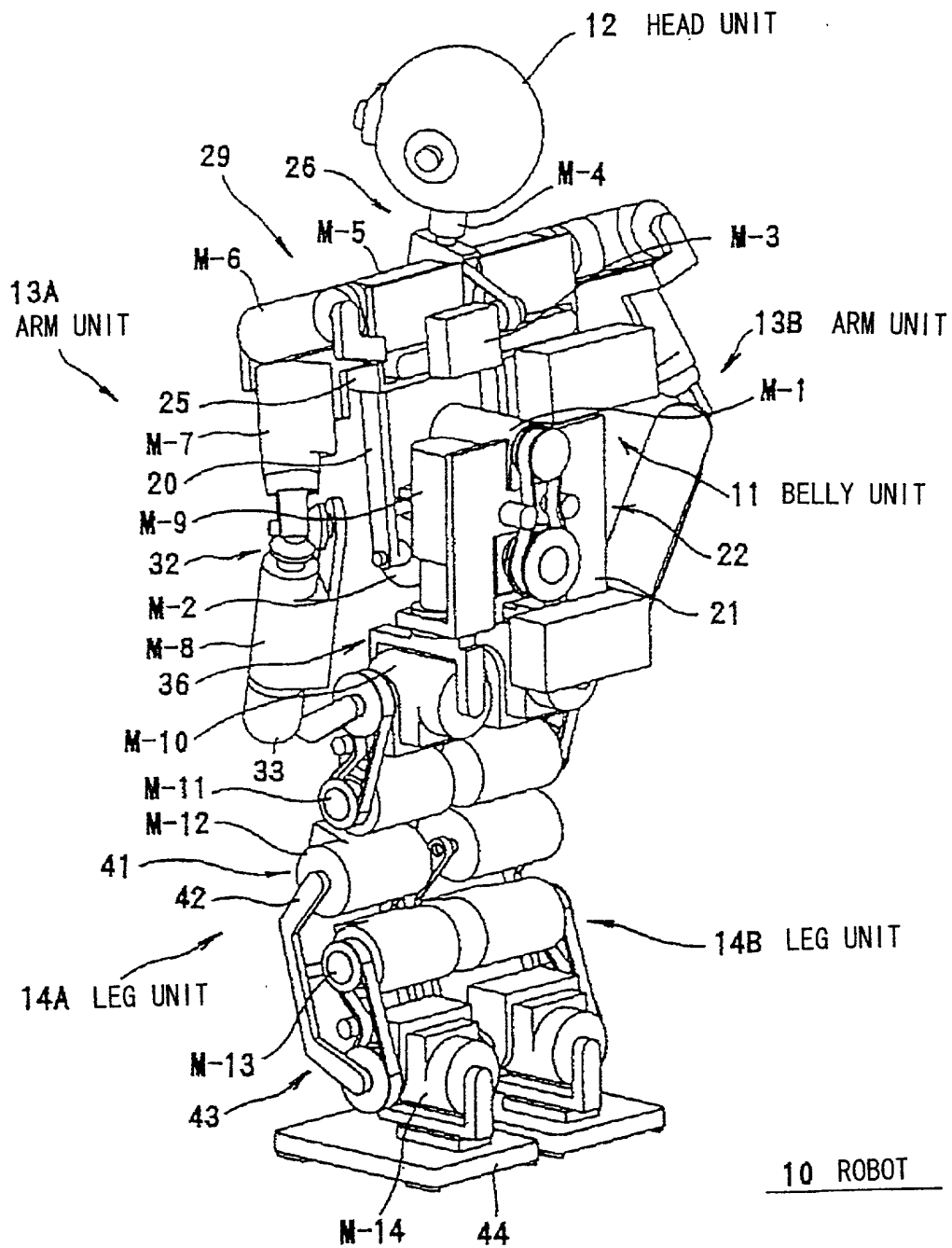


FIG. 2

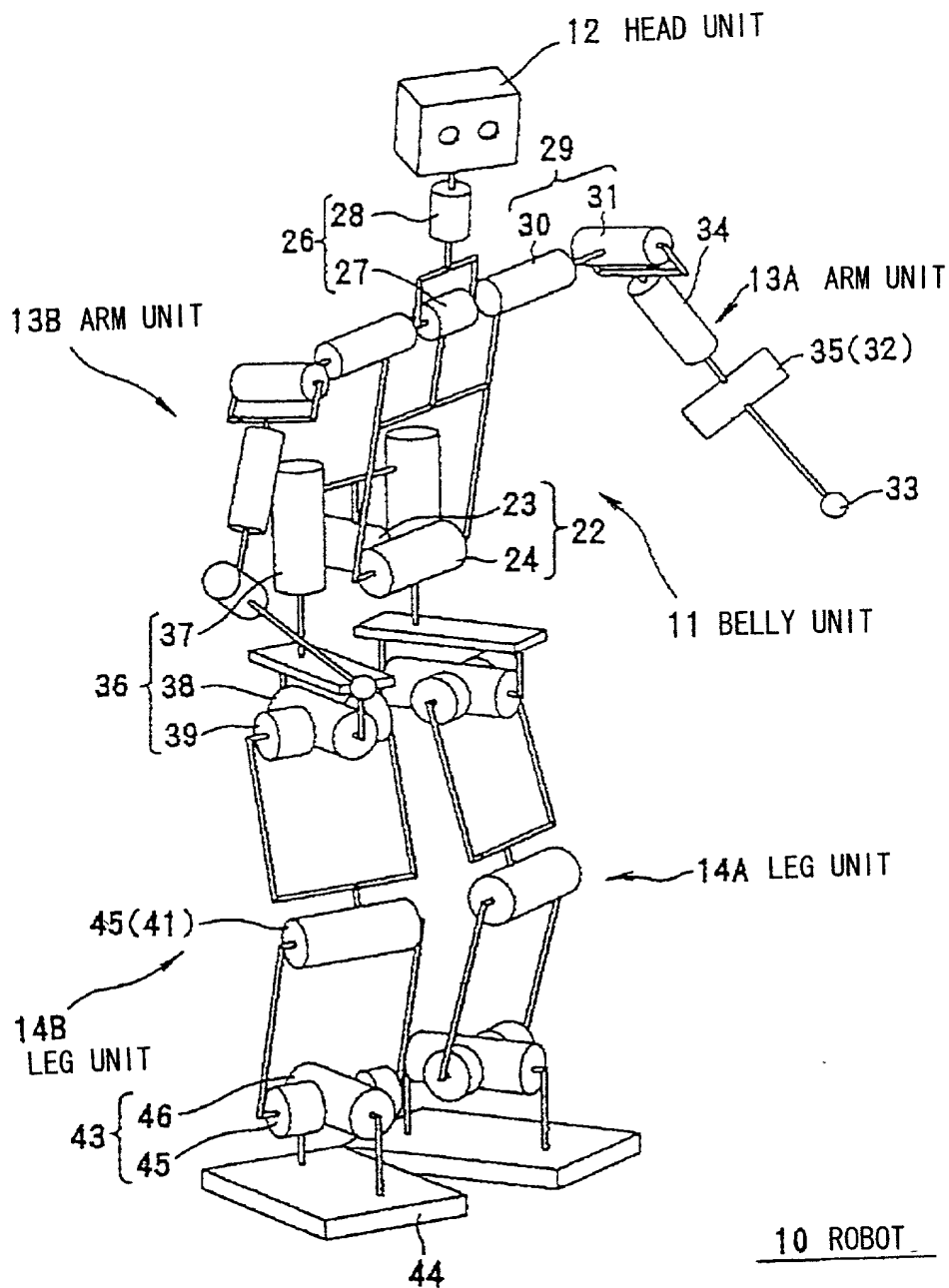
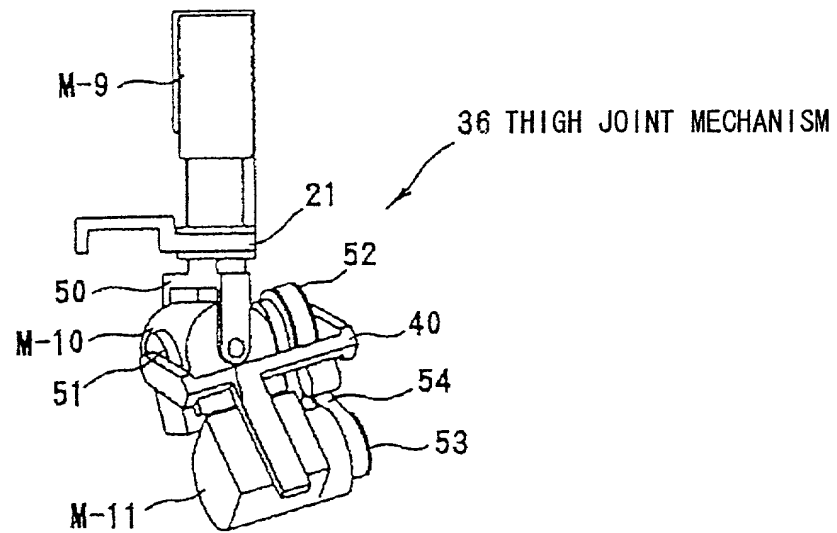


FIG. 3

(A)



(B)

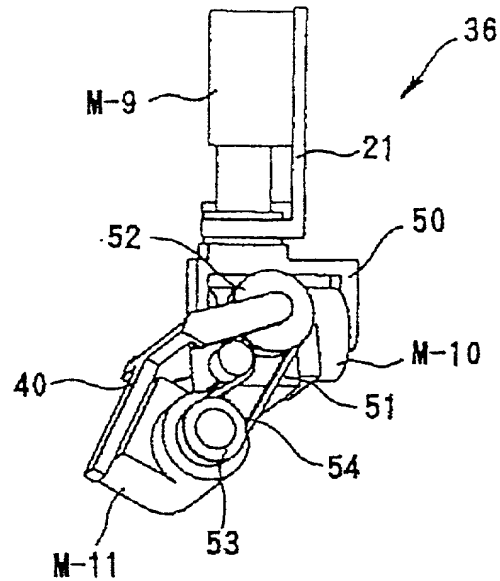


FIG. 4

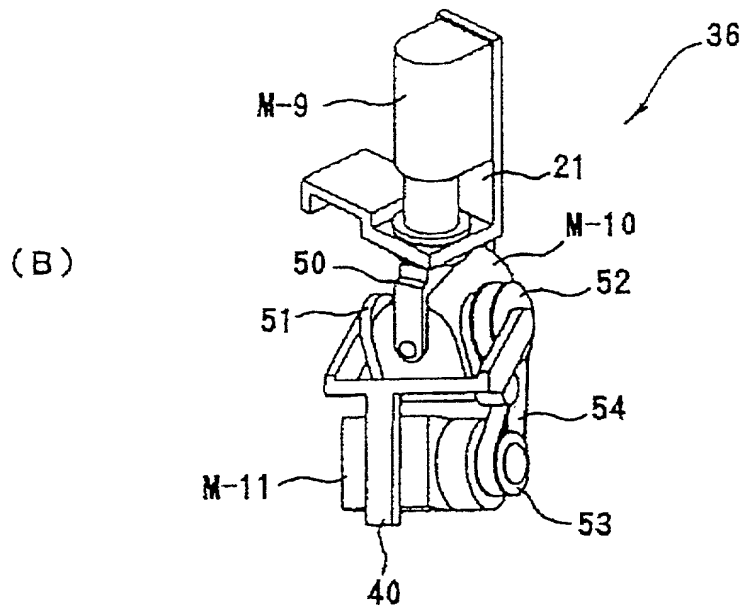
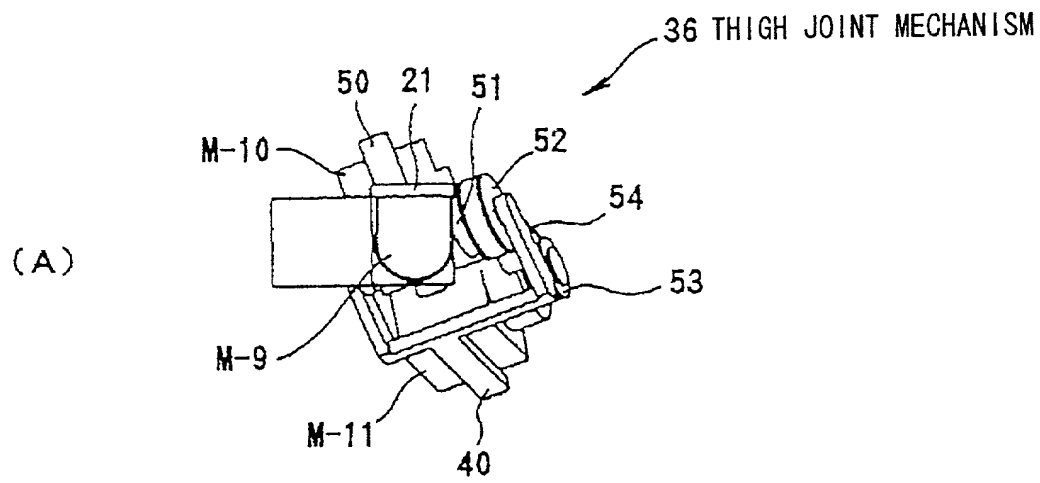


FIG. 5

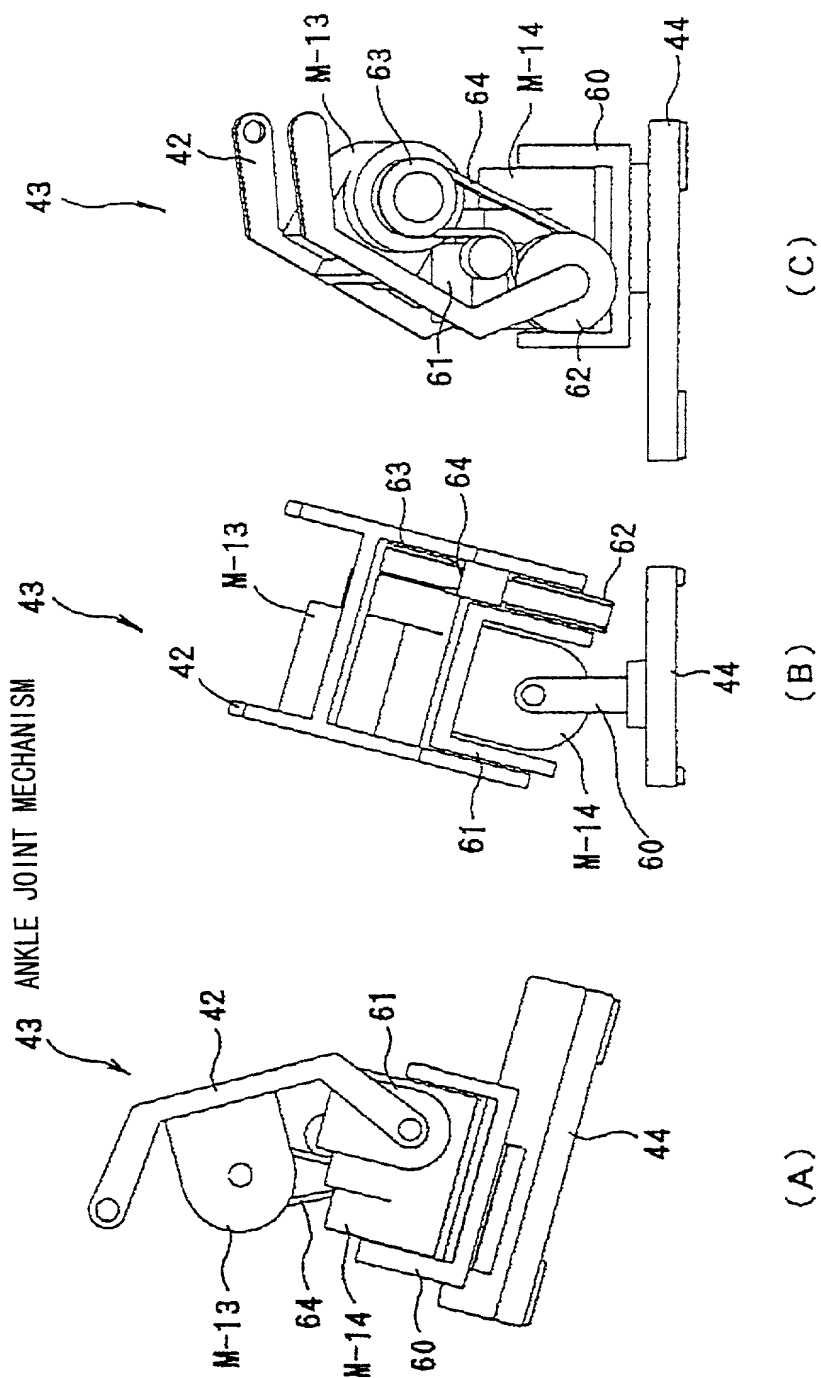


FIG. 6

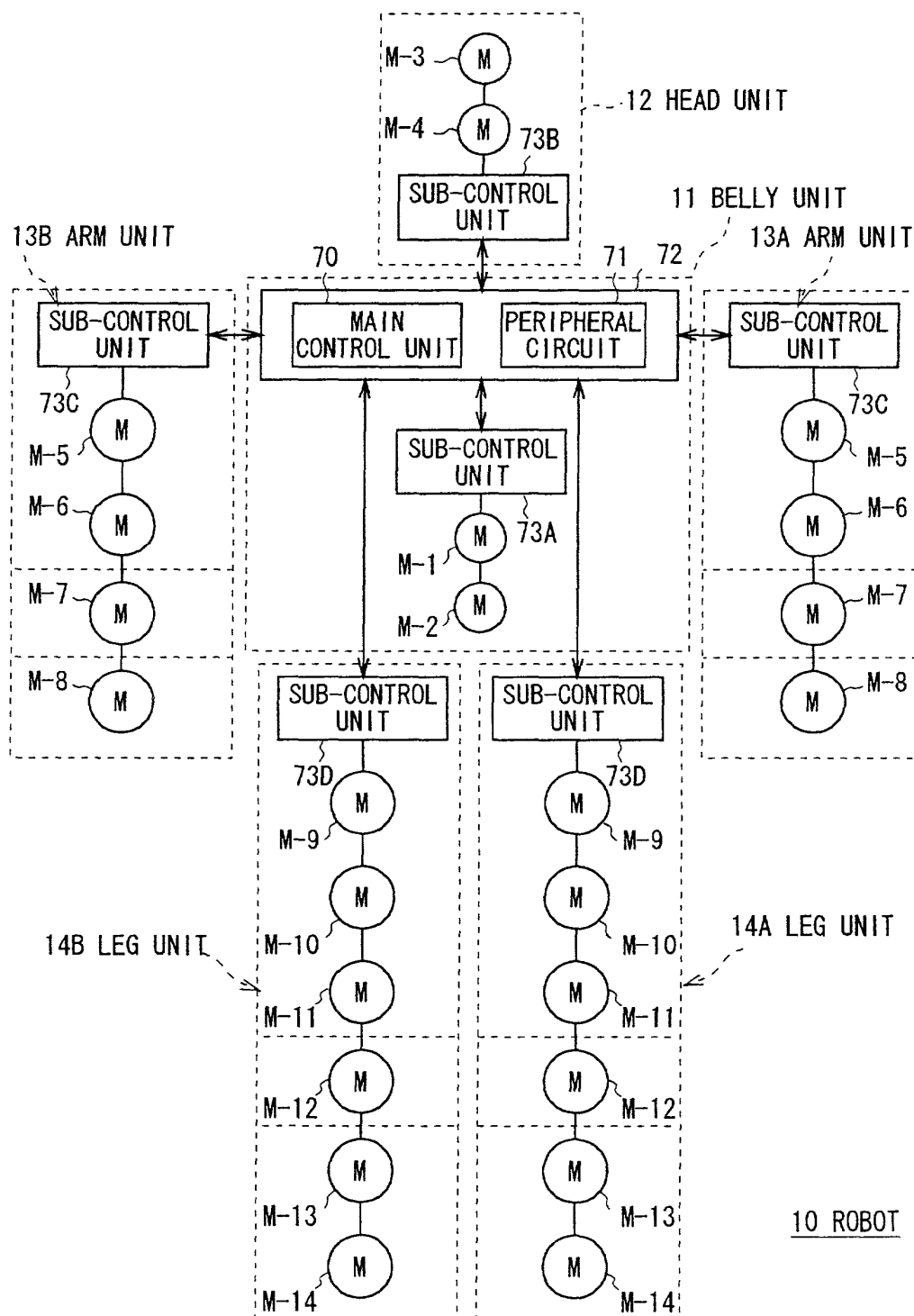
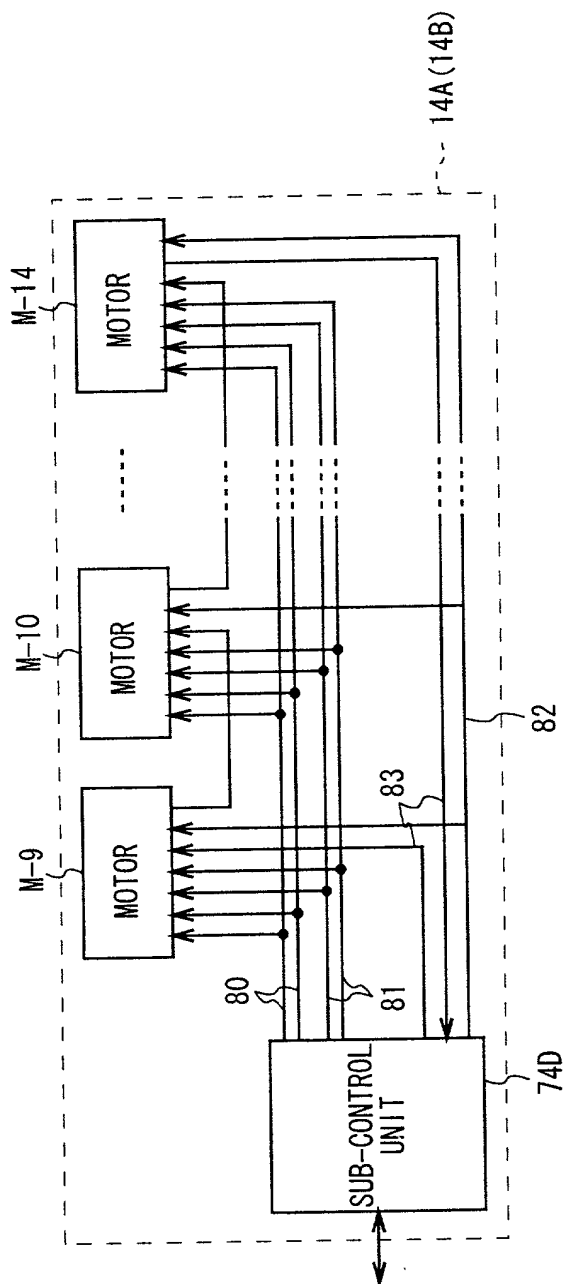


FIG. 7



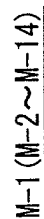


FIG. 9

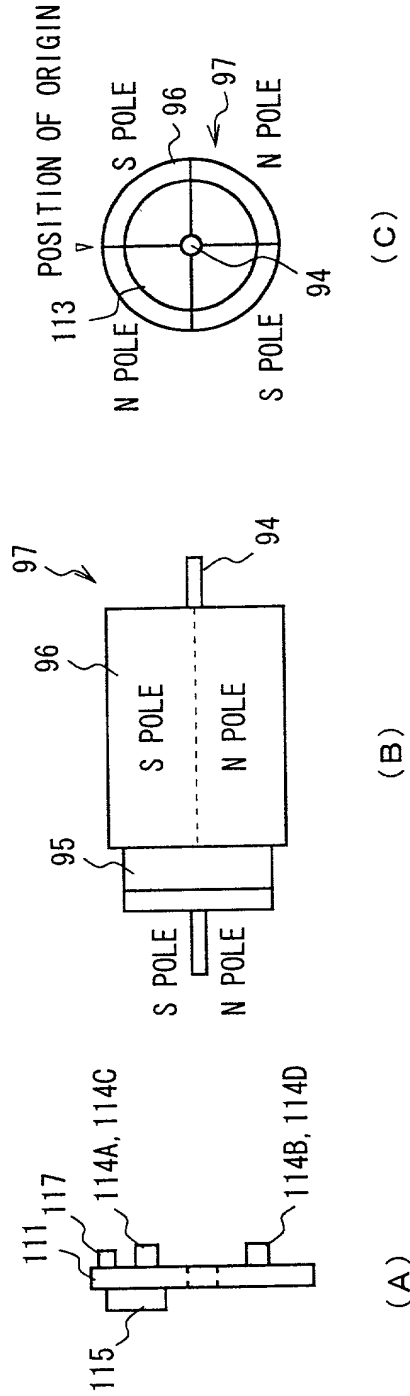


FIG. 10

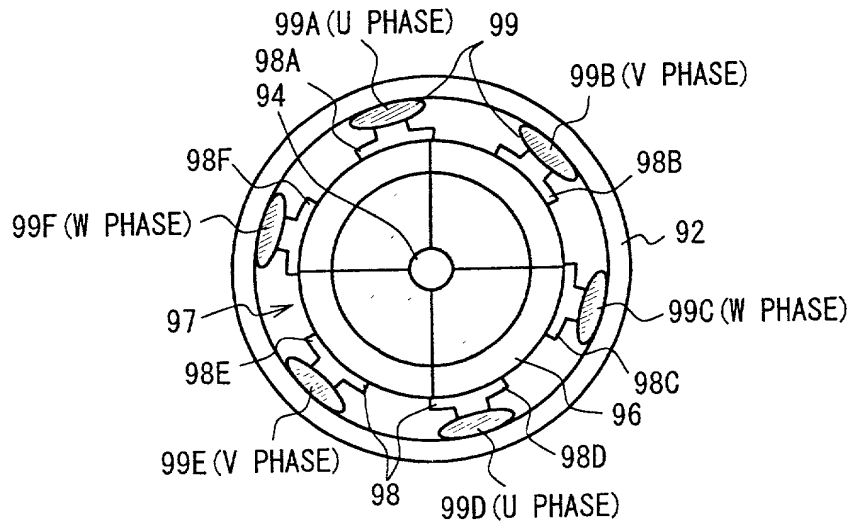


FIG. 11

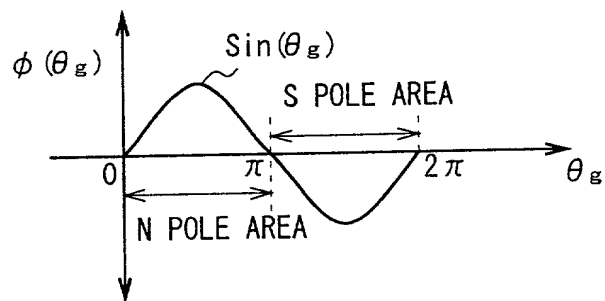


FIG. 14

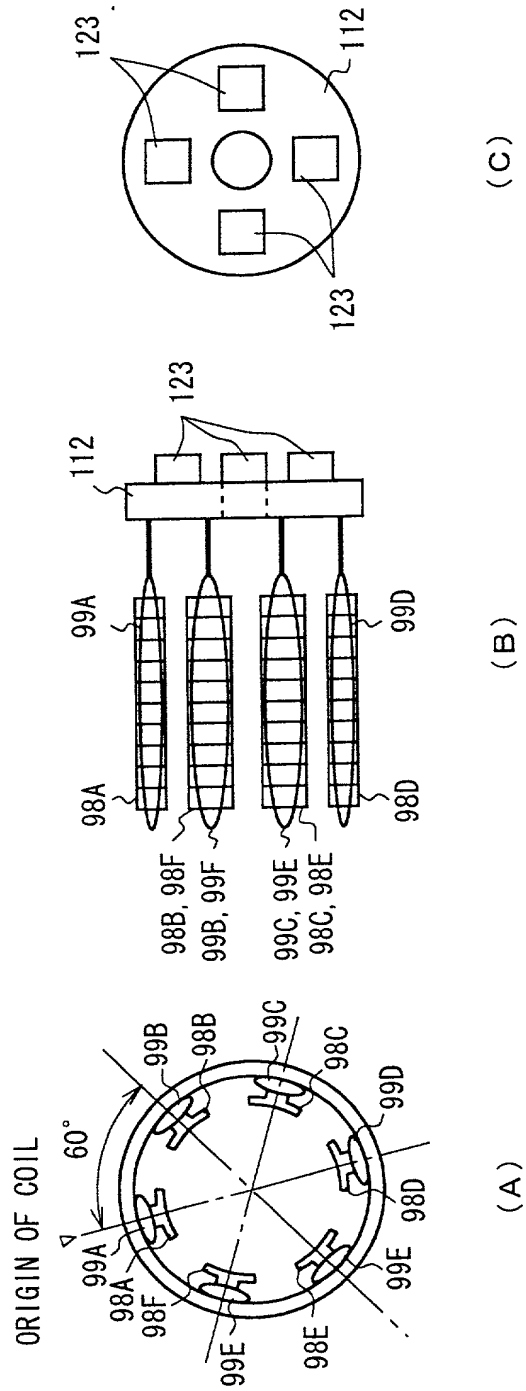


FIG. 12

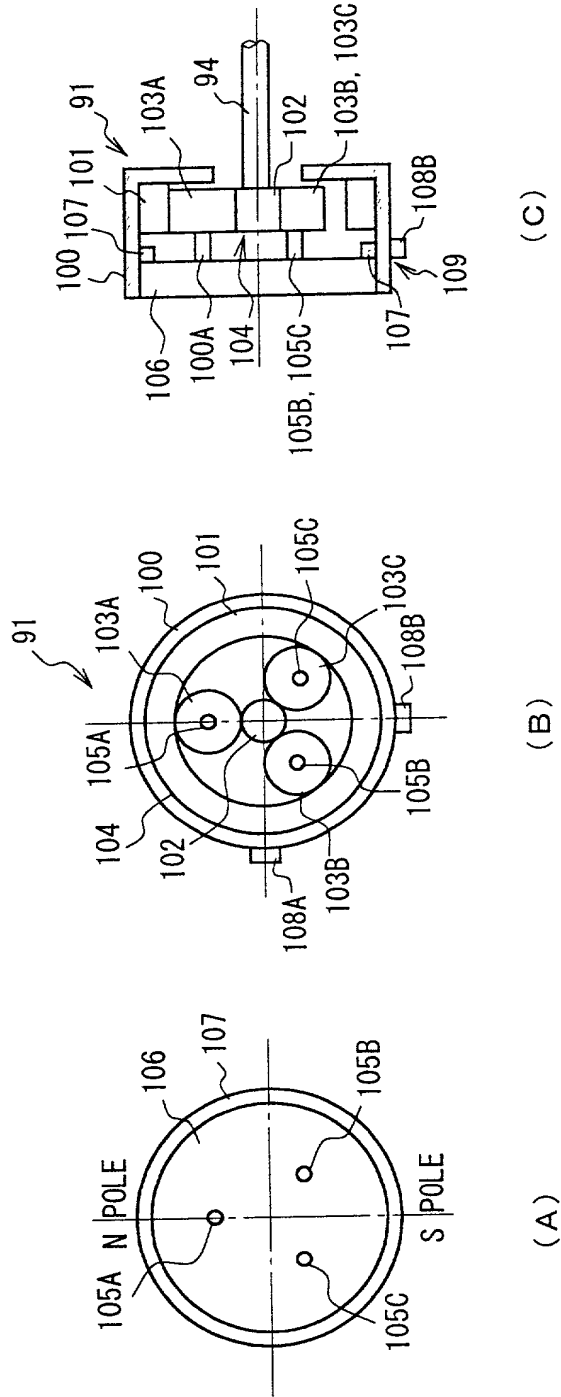


FIG. 13

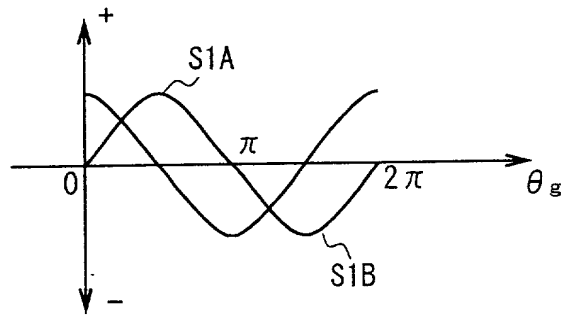


FIG. 15

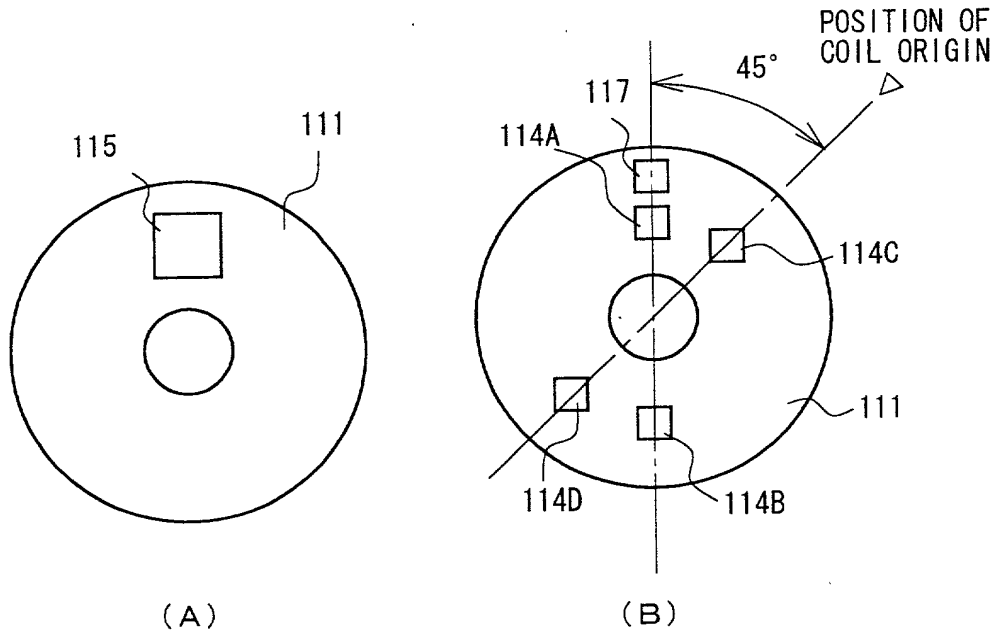


FIG. 16

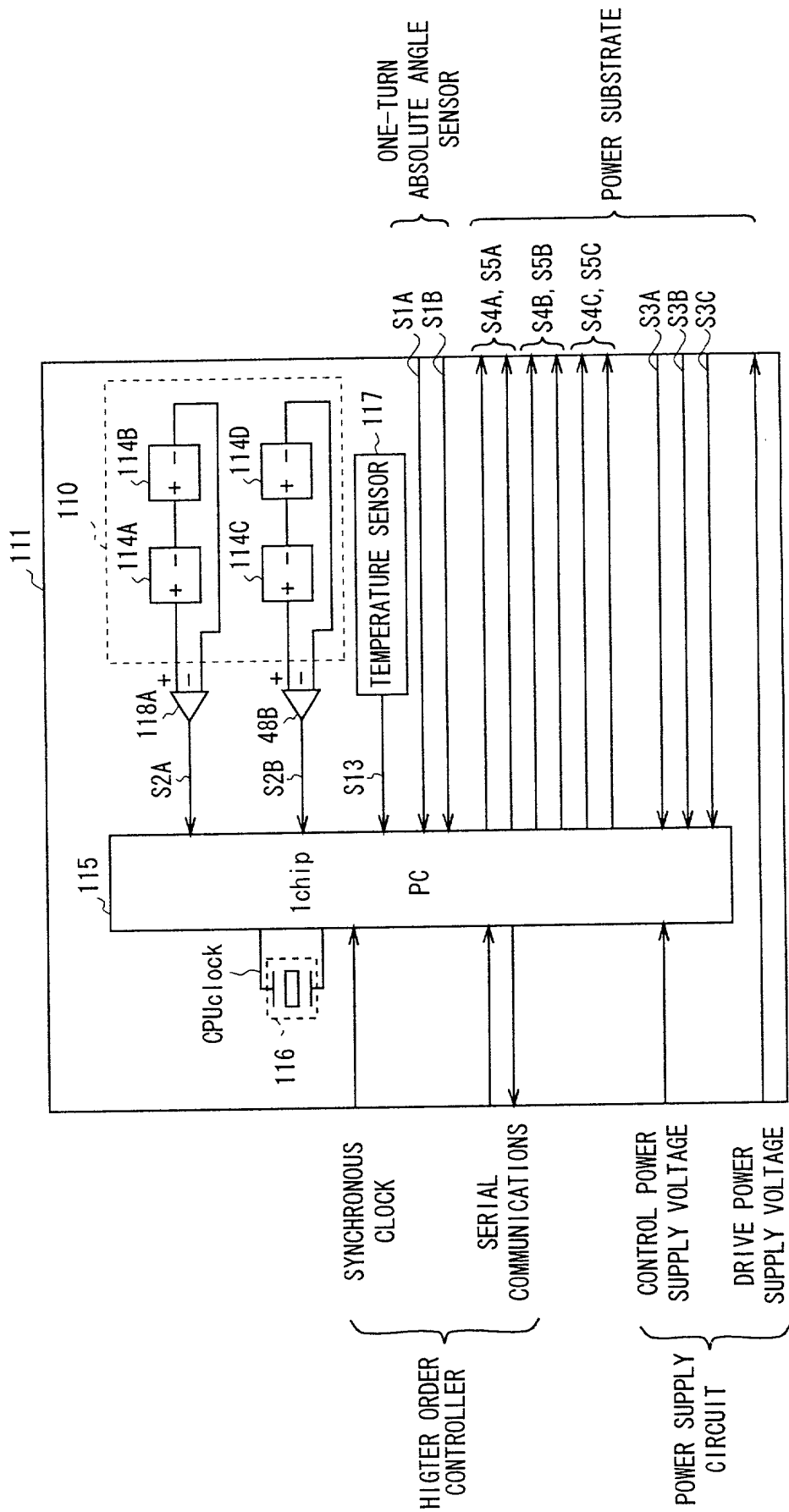


FIG. 17

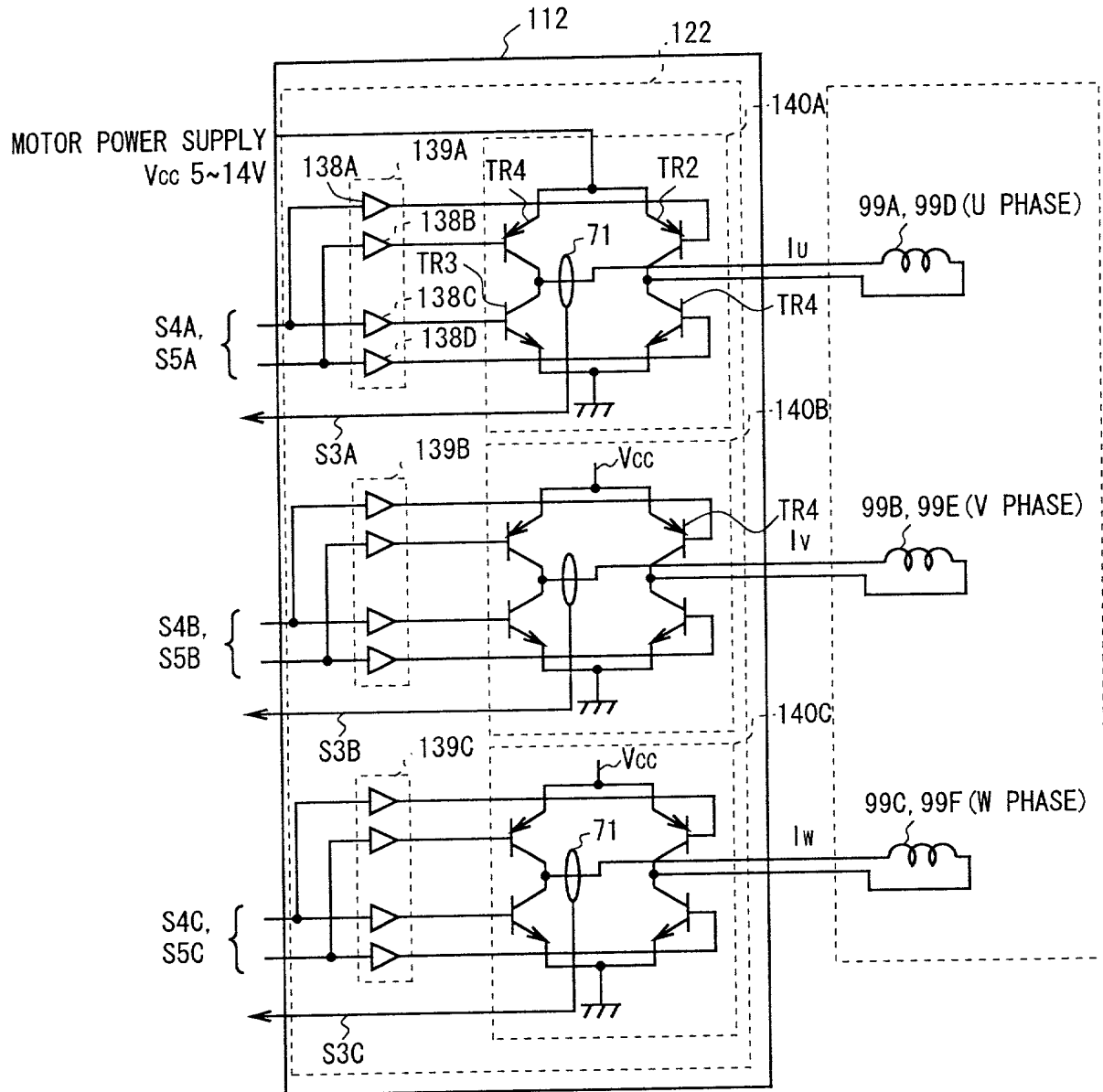


FIG. 18

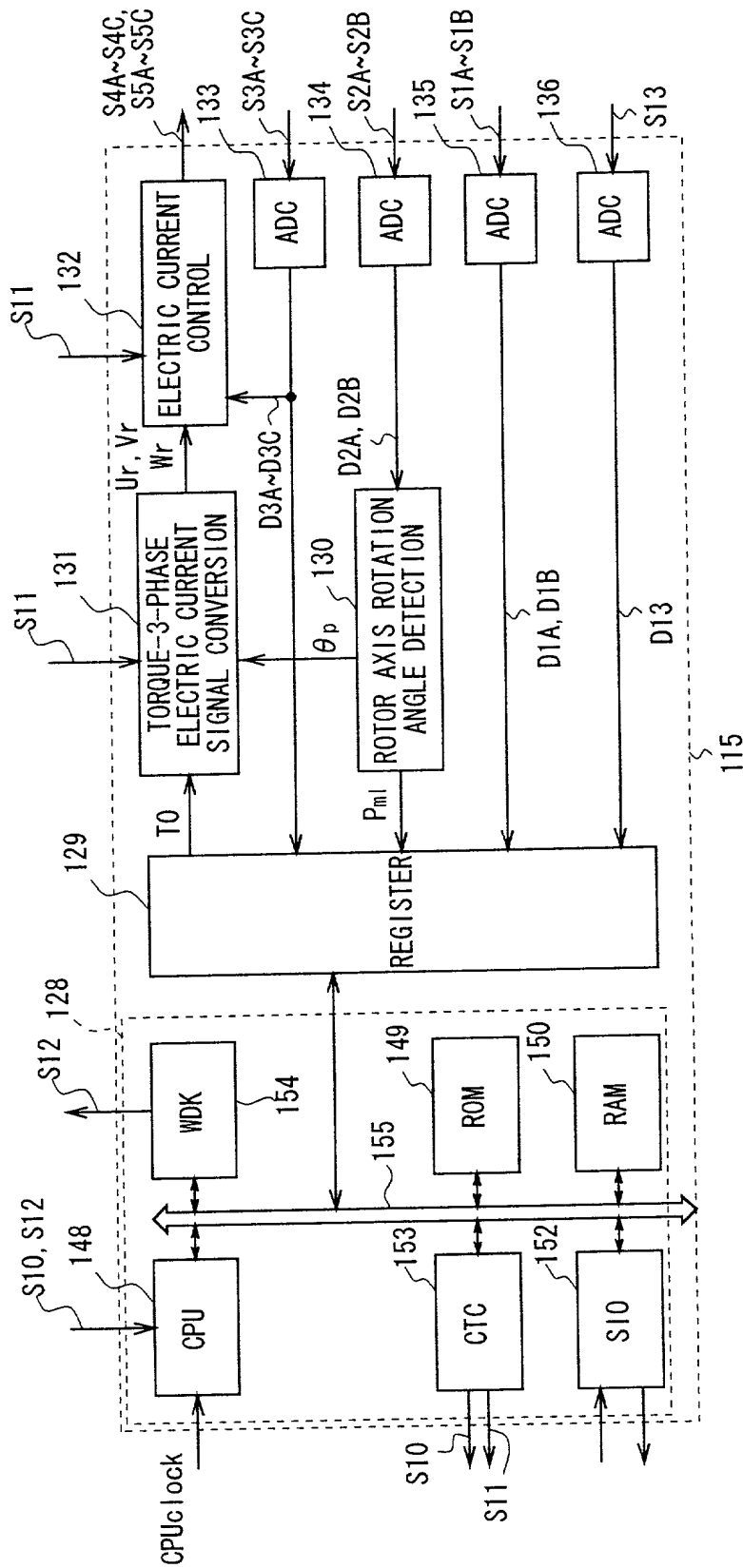


FIG. 19

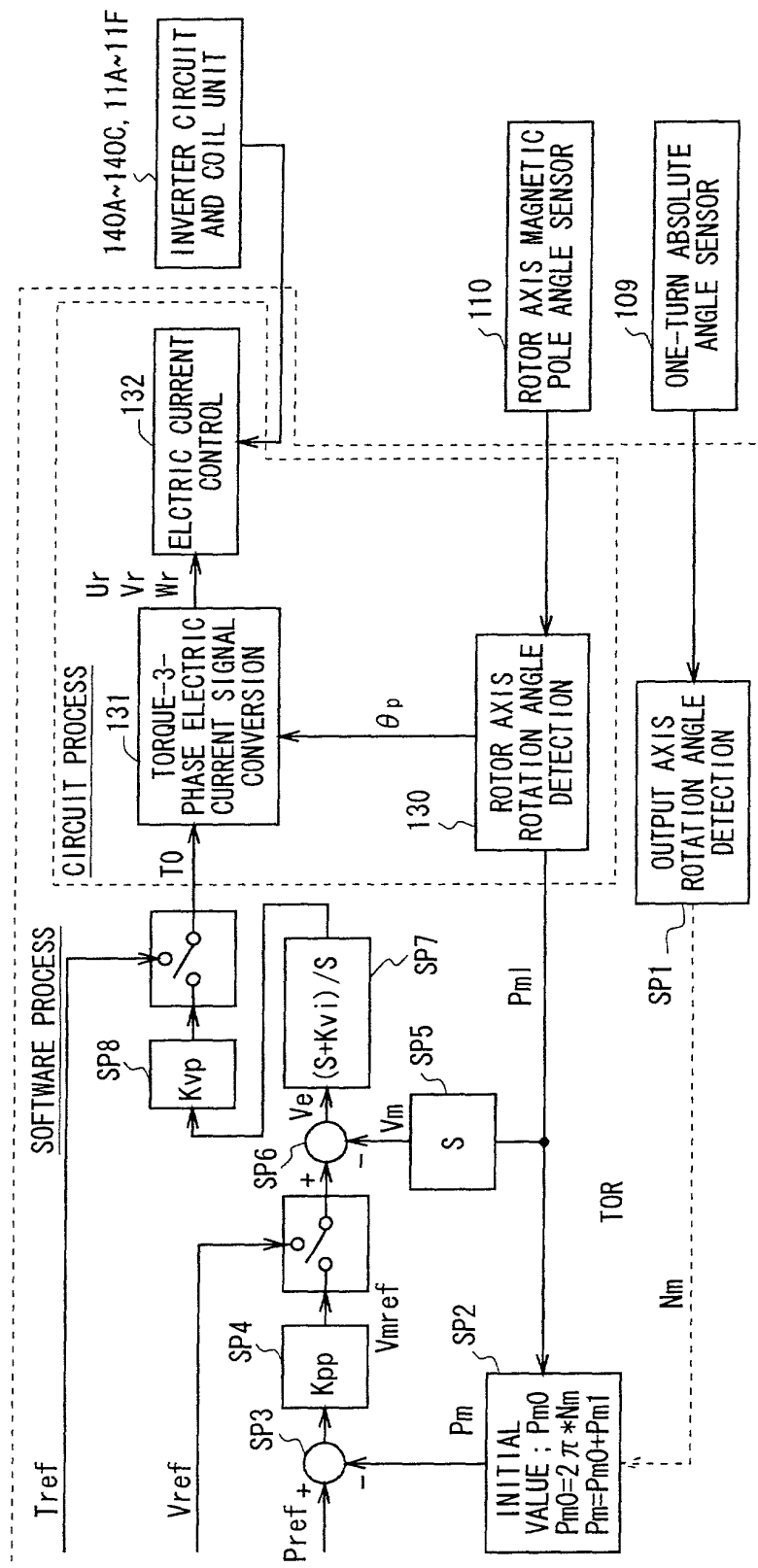


FIG. 20

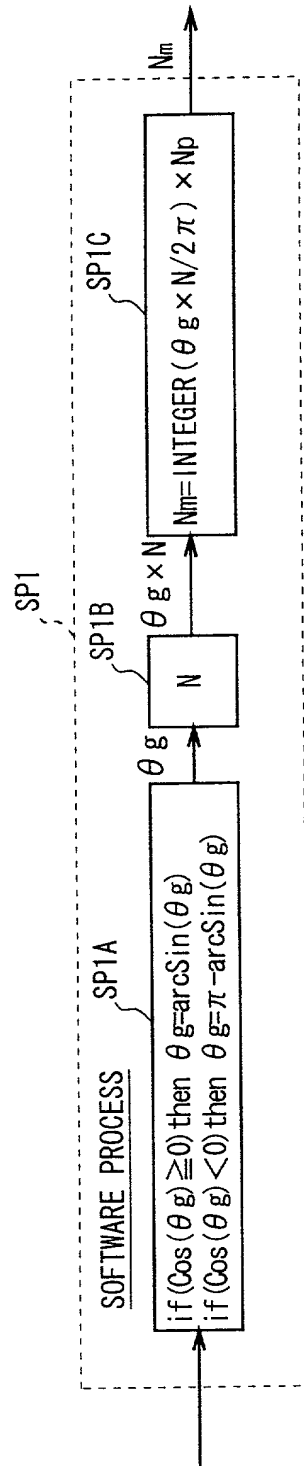


FIG. 21

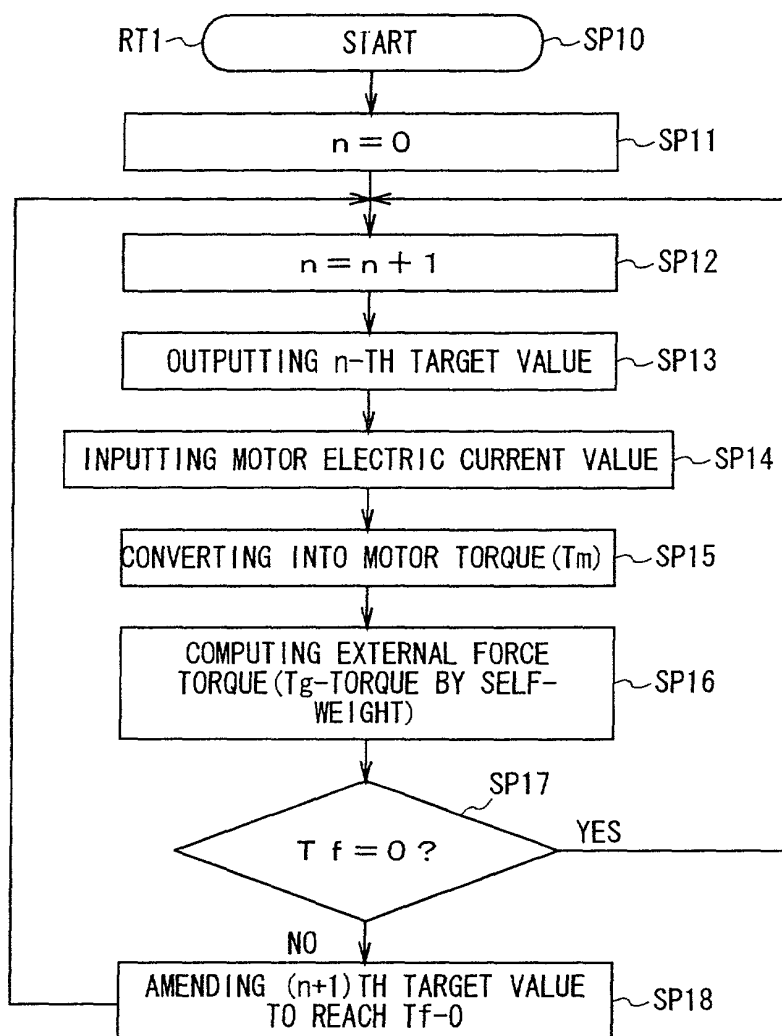


FIG. 22

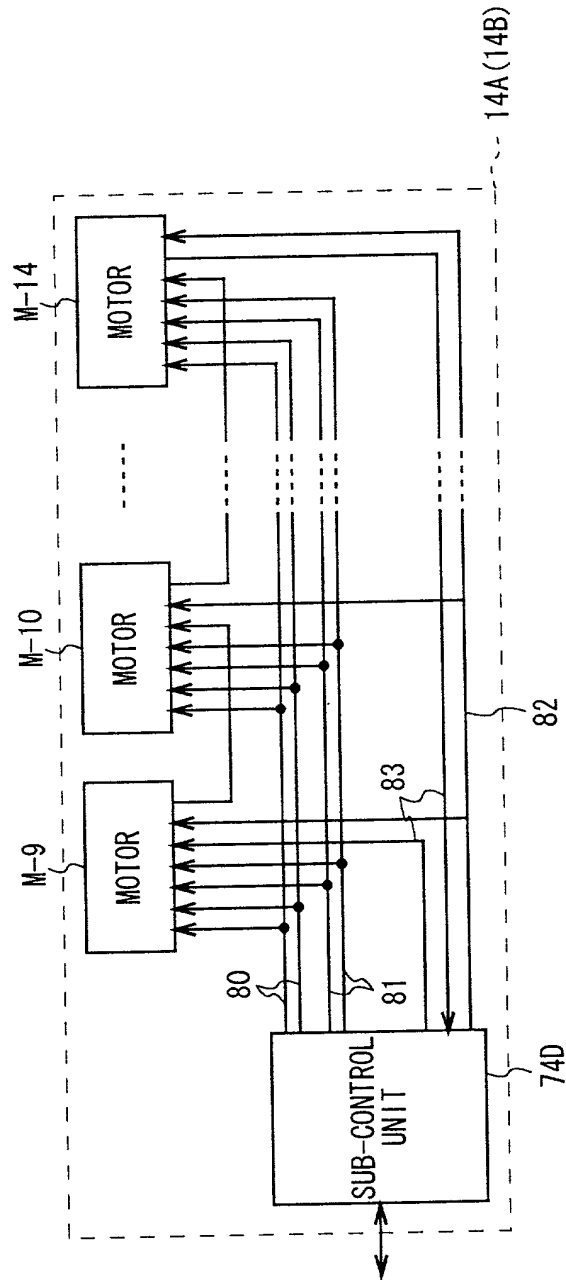


FIG. 23

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# Explanation of Reference Numerals

10...robot, 11...belly unit, 12...head unit, 13A, 13B...arm units,  
14A, 14B...leg units, 43...ankle joint mechanism, 44...foot unit,  
70...main control unit, 73A through 73D...sub-control units,  
106...output axis, 111...control substrate, 112...power substrate,  
148...CPU, M-1 through M-14...motors, and RT1...unleveled ground  
walking controlling procedure.

09/646849 - 10/2000

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U.S. Appln. No. 09/646,849

TNAB-T0158

## Declaration and Power of Attorney For Patent Application

## 特許出願宣言書及び委任状

## Japanese Language Declaration

## 日本語宣言書

下記の氏名の発明者として、私は以下の通り宣言します。	As a below named inventor, I hereby declare that:
私の住所、私書箱、国籍は下記の私の氏名の後に記載された通りです。	My residence, post office address and citizenship are as stated next to my name.
下記の名称の発明に関して請求範囲に記載され、特許出願している発明内容について、私が最初かつ唯一の発明者（下記の氏名が一つの場合）もしくは最初かつ共同発明者であると（下記の名称が複数の場合）信じています。	I believe I am the original, first and sole inventor (if only one named is listed below) or an original, first and joint inventor (if plural names are listed below) of the subject matter which is claimed and for which a patent is sought on the invention entitled.  APPARATUS AND METHOD FOR JOINT MECHANISM, JOINT APPARATUS, AND ROBOT DEVICE AND CONTROL METHOD THEREOF
上記発明の明細書（下記の欄でx印がついていない場合は、本書に添付）は、 <input type="checkbox"/> 月 日に提出され、米国出願番号または特許協定条約国際出願番号を _____ とし、 （該当する場合） _____ に訂正されました。	the specification of which is attached hereto unless the following box is checked:  <input checked="" type="checkbox"/> was filed on <u>February 10, 2000</u> as United States Application Number or PCT International Application Number <u>PCT/JP00/00754</u> and was amended on _____ (if applicable).
私は、特許請求範囲を含む上記訂正後の明細書を検討し、内容を理解していることをここに表明します。	I hereby state that I have reviewed and understand the contents of the above identified specification, including the claims, as amended by any amendment referred to above.
私は、連邦規則法典第37編第1条56項に定義されるとおり、特許資格の有無について重要な情報を開示する義務があることを認めます。	I acknowledge the duty to disclose information which is material to patentability as defined in Title 37, Code of Federal Regulations, Section 1.56.
私は、米国法典第35編119条(a)-(d)項又は365条(b)項に基づき下記の、米国以外の国の少なくとも一カ国を指定している特許協力条約365(a)項に基づき国際出願、又は外国での特許出願もしくは発明者証の出願についての外国優先権をここに主張するとともに、優先権を主張している、本出願の前に出願された特許または発明者証の外国出願を以下に、枠内をマークすることで、示しています。	I hereby claim foreign priority under Title 35, United States Code, Section 119(a)-(d) or 365(b) of any foreign application(s) for patent or inventor's certificate, or 365(a) of any PCT International application which designated at least one country other than the United States, listed below and have also identified below, by checking the box, any foreign application for patent or inventor's certificate, or PCT International application having a filing date before that of the application on which priority is claimed.
Prior Foreign Application(s) 外国での先行出願  P11-033385 (Number) (番号)	Priority Not Claimed 優先権主張なし  10 February 1999 (Day/Month/Year Filed) (出願年月日)
Japan (Country) (国名)	

<p align="center"><b>Japanese Language Declaration</b> 日本語宣言書</p>			
<p>P11-254880 (Number) (番号)</p>	<p>Japan (Country) (国名)</p>	<p>8 September 1999 (Day/Month/Year Filed) (出願年月日)</p>	
<p>私は、第35編米国法典119条(e)項に基いて下記の米 国特許出願規定に記載された権利をここに主張いたします。</p>		<p>I hereby claim the benefit under Title 35, United States Code, Section 119(e) of any United States provisional application(s) listed below.</p>	
<p>(Application No.) (出願番号)</p>	<p>(Filing Date) (出願日)</p>	<p>(Application No.) (出願番号)</p>	<p>(Filing Date) (出願日)</p>
<p>私は、下記の米国法典第35編120条に基いて下記の米 国特許出願に記載された権利、又は米国を指定している特許 協力条約365条(c)に基づき権利をここに主張します。ま た、本出願の各請求範囲の内容が米国法典第35編112条 第1項又は特許協力条約で規定された方法で先行する米国特 許出願に開示されていない限り、その先行米国出願書提出日 以降で本出願書の日本国内または特許協力条約国際提出日ま での期間中に入手された、連邦規則法典第37編1条56項 で定義された特許資格の有無に関する重要な情報について開 示義務があることを認識しています。</p>		<p>I hereby claim the benefit under Title 35, United States Code, Section 120 of any United States application(s), or 365(c) of any PCT International application designating the United States, listed below and, insofar as the subject matter of each of the claims of this application is not disclosed in the prior United States or PCT International application in the manner provided by the first paragraph of Title 35, United States Code, Section 112, I acknowledge the duty to disclose information which is material to patentability as defined in Title 37, Code of Federal Regulations, Section 1.56 which became available between the filing date of the prior application and the national or PCT International filing date of application.</p>	
<p>(Application No.) (出願番号)</p>	<p>(Filing Date) (出願日)</p>	<p>(Status: Patented, Pending, Abandoned) (現況: 特許許可済、係属中、放棄済)</p>	
<p>(Application No.) (出願番号)</p>	<p>(Filing Date) (出願日)</p>	<p>(Status: Patented, Pending, Abandoned) (現況: 特許許可済、係属中、放棄済)</p>	
<p>私は、私自身の知識に基づいて本宣言書中で私が行なう表 明が真実であり、かつ私の入手した情報と私の信じるところ に基づき表明が全て真実であると信じていること、さらに故 意になされた虚偽の表明及びそれと同等の行為は米国法典第 18編第1001条に基づき、罰金または拘禁、もしくはそ の両方により処罰されること、そしてそのような故意による 虚偽の声明を行なえば、出願した、又は既に許可された特許 の有効性が失われることを認識し、よってここに上記のごと く宣誓を致します。</p>		<p>I hereby declare that all statements made herein of my own knowledge are true and that all statements made on information and belief are believed to be true; and further that these statements were made with the knowledge that willful false statements and the like so made are punishable by fine or imprisonment, or both, under Section 1001 of Title 18 of the United States Code and that such willful false statements may be jeopardize the validity of the application or any patent issued thereon.</p>	

## Japanese Language Declaration

日本語宣言書

委任状： 私は下記の発明者として、本出願に関する一切の手続きを米特許商標局に対して遂行する弁理士または代理人として、下記の者を指名いたします。（弁理士、または代理人の氏名及び登録番号を明記のこと）

POWER OF ATTORNEY: As a named inventor, I hereby appoint the following attorney(s) and/or agent(s) to prosecute this application and transact all business in the Patent and Trademark office connected therewith (list name and registration number)

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John K. Uilkema	20,282	Mark C. Pickering	36,239	Charles L. Hamilton	42,624
Neil A. Smith	25,441	Patricia Coleman James	37,155	Andrew V. Smith	43,132
Veronica C. Devitt	29,375	Kathleen A. Frost	37,326	Eric N. Hoover	37,355
Ronald L. Yin	27,607	Alan A. Limbach	39,749	Frank J. Mycroft	P-46,946
Gerald T. Sekimura	30,103	Douglas C. Limbach	35,249	Parisa Jorjani	P-46,813
Michael A. Stallman	29,444	Seong-Kun Oh*		Robert M. McConnell	P-46,912
Philip A. Girard	28,848	Cameron A. King	41,897	J. Thomas McCarthy	22,420
Michael J. Pollock	29,098	Kyla L. Harriel	41,815	Joel G. Ackerman	24,307
Steven M. Everett	30,050	Mayumi Maeda	40,075	Susan M. Schmitt	34,427
				Edward B. Weller	37,468

\* Recognition under 37 CFR 10.9(b)

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